

(12) INTERNATIONAL APPLICATION PUBLISHED UNDER THE PATENT COOPERATION TREATY (PCT)

(19) World Intellectual Property Organization
International Bureau(43) International Publication Date
17 April 2003 (17.04.2003)

PCT

(10) International Publication Number
WO 03/032627 A1

(51) International Patent Classification⁷: H04N 3/15 (81) Designated States (national): AE, AG, AL, AM, AT (utility model), AT, AU, AZ, BA, BB, BG, BR, BY, BZ, CA, CH, CN, CO, CR, CU, CZ (utility model), CZ, DE (utility model), DE, DK (utility model), DK, DM, DZ, EC, EE (utility model), EE, ES, FI (utility model), FI, GB, GD, GE, GH, GM, HR, HU, ID, IL, IN, IS, JP, KE, KG, KP, KR, KZ, LC, LK, LR, LS, LT, LU, LV, MA, MD, MG, MK, MN, MW, MX, MZ, NO, NZ, OM, PH, PL, PT, RO, RU, SD, SE, SG, SI, SK (utility model), SK, SL, TJ, TM, TN, TR, TT, TZ, UA, UG, US, UZ, VC, VN, YU, ZA, ZM, ZW.

(21) International Application Number: PCT/DK02/00589 (22) International Filing Date: 11 September 2002 (11.09.2002)

(25) Filing Language: English (26) Publication Language: English

(30) Priority Data: PA 2001 01326 12 October 2001 (12.10.2001) DK (71) Applicant (for all designated States except US): DELTAPIX APS [DK/DK]; Gulddyssevænget 3, Gundsmøagle, DK-4000 Roskilde (DK).

(72) Inventor; and (75) Inventor/Applicant (for US only): ANDERSEN, Steen, Ørsted [DK/DK]; Gulddyssevænget 3, Gundsmøagle, DK-4000 Roskilde (DK).

(74) Agent: HOLME PATENT A/S; Vesterbrogade 20, DK-1620 Copenhagen V (DK).

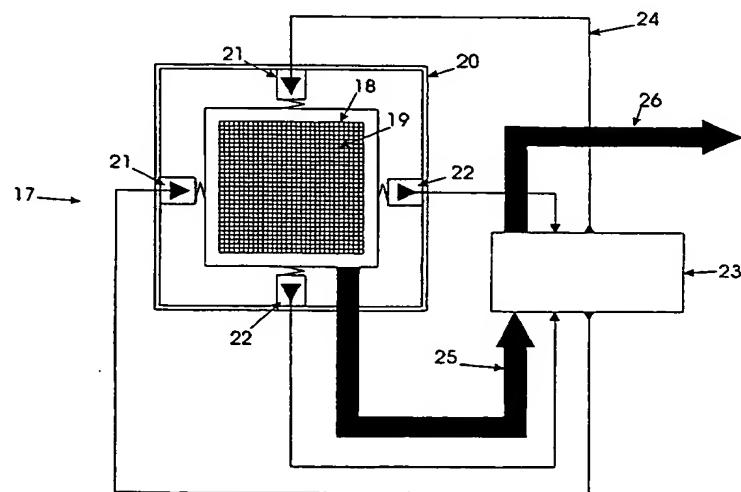
(84) Designated States (regional): ARIPO patent (GH, GM, KE, LS, MW, MZ, SD, SL, SZ, TZ, UG, ZM, ZW), Eurasian patent (AM, AZ, BY, KG, KZ, MD, RU, TJ, TM), European patent (AT, BE, BG, CH, CY, CZ, DE, DK, EE, ES, FI, FR, GB, GR, IE, IT, LU, MC, NL, PT, SE, SK, TR), OAPI patent (BF, BJ, CF, CG, CI, CM, GA, GN, GQ, GW, ML, MR, NE, SN, TD, TG).

Published:

— with international search report
— with amended claims

[Continued on next page]

(54) Title: A METHOD AND APPARATUS FOR PRODUCING A HIGH RESOLUTION IMAGE



(57) Abstract: A method and apparatus serves for converting a low resolution first image to a high resolution second image. The apparatus is comprising a light sensor (1, 19) for receiving incident light radiated from a scene. The light sensor has a number of cells, each defining a predetermined area, and is arranged for cyclically scanning the low resolution first image a number of times while at least one driver (21, 33, 39, 40) is moving the light sensor an identical number of times in at least one direction. For each step the light sensor is moved a distance corresponding to the extend of the area covered by the cell in the direction of movement while the total distance covered corresponds to the extend of the cell in said direction. Thereby a number of subareas are defined. A computer (23, 35) serves for establishing a representation of the high resolution second image by calculating the representation of the received incident light from the scene at each subarea by means of a software program. Thereby is obtained a higher resolution and a better image quality than hitherto known.

WO 03/032627 A1

BUREAU M.P.J. COCKSTAEL N.V.
Arenbergstraat 13
B-2000 ANTWERPEN
Tel.: 03 / 255.00.60
Fax.: 03 / 233.71.62

BEST AVAILABLE COPY



For two-letter codes and other abbreviations, refer to the "Guidance Notes on Codes and Abbreviations" appearing at the beginning of each regular issue of the PCT Gazette.

A method and apparatus for producing a high resolution image

The present invention relates to a method and an apparatus for producing a high-resolution image.

5

Solid state imaging devices such as CCDs (Charge Coupled Devices) or C-MOS arrays consisting of imaging surfaces, with pixels arranged in a one or two-dimensional matrix are widely used in digital cameras and scanners.

10

There is however a growing demand for higher resolution of the images. One way of obtaining a higher resolution is by increasing the number of pixels in the imaging surface of solid state imaging devices. However, if the number of pixels 15 is simply increased in e.g. a CCD to satisfy the need for high resolution, its chip size has to be further increased. On the other hand, in order to increase the number of pixels without changing the present CCD chip size, the integration of pixels must be greatly enhanced. It is technically difficult to 20 prepare such a high-density CCD. Even if development of improved fabrication techniques allows the manufacture of such a CCD in the near future, the circuit configuration for driving such a CCD becomes complicated and power consumption becomes higher, thus entailing new problems, which will result 25 in loss of production efficiency and higher cost.

Other methods for obtaining higher resolution have been used. In scanners the CCD or CMOS array are usually moved in one direction in steps equal to the height of the individual 30 sensors by means of stepper motors, and in special high resolution cameras, the sensor matrix are moved in both an X and an Y directions, to move the individual cells to positions not covered by any cell in the matrix (due to a physical distance between each sensor) or to positions not covered by 35 either a red, green or blue filtered cell. All methods have

the limitation that the area of each sensor-cell is limiting the achievable resolution.

US 6,002,810 disclose a method for generating an image having an arbitrary number of pixels starting from a given digitally image having a given number of pixels. This method does not provide a means for improving the resolution and the quality of the image after enlarging will be inferior to the original.

5 US 4,652,928 relate to a method for improving the actual resolution of an image at the time the image is being established. However, the improvement of the resolution is limited by a factor 2 and is effected solely upon movement in a horizontal direction. Moreover, as already mentioned the 10 achievable resolution is limited by the size of the sensor-cells.

15

WO 9712483 discloses an array of CCD cameras, which by means of micro-motion mechanisms moves the array such that a number 20 of images are scanned, thereafter the images are combined to form one high-resolution image. It does not, however, disclose a technical solution to create a high-resolution image from the scanned images.

25 US 5,754,226 disclose a method to generate a high-resolution image based on a number of displaced low-resolution images. However the accuracy of the method requires that no frequency components above $1/Ph$ occur to avoid aliasing. To efficiently remove frequencies above $1/Ph$ a birefringence plate is used 30 which both increases the costs and by removing frequencies above $1/Ph$ in the low-resolution image also excludes the possibility to regenerate information above this frequency in the high-resolution image.

35 It is therefore an object of the present invention to provide a new and improved method and apparatus capable of attaining

higher resolution and realising better image quality cheaper than known up till now.

According to the invention a low resolution first image is
5 converted to a high resolution second image by means of a light sensor for receiving incident light radiated from a scene, whereby said light sensor is constructed as an array or a matrix having a number of cells, each defining a predetermined area.

10 The method for carrying out said converting is comprising that said first image is cyclically scanned a number of times, that the light sensor simultaneously with the scanning stepwise is moved an identical number of times relative to the light
15 radiating scene in at least one direction thereby defining a number of subareas, that the total distance covered during movement of the light sensor corresponds to the extend of the cell or to the extend of the cell plus a distance defined by or to the neighbour cell in said at least one direction, and
20 that a representation of the high resolution second image is established by calculating the representation of the received incident light from the scene at each subarea.

25 Thereby a method advantageously is obtained in which the calculations are limited to a minimum but were the image resolution is only limited by factors as optics and precision of the positioning mechanism and not by the number and size of each sensor cell, thus giving the possibility of achieving an extremely high resolution, not known by any other method.

30 The calculating representing the received incident light from the scene at each subarea can advantageously be performed by means of a computer having a software program for receiving the output from the position sensor and on basis of this
35 output calculate control values for bringing the light sensor to move in a wanted way.

If the light sensor for each step is moved a distance corresponding to the extend of the area covered by the cell in the direction of movement, divided with the number of scanning 5 times it is possible, due to the overlapping between the scannings, to have several scannings on the same cell whereby the calculations in the cycle and thus the resolution will become even more accurate.

10 By an advantageously embodiment according to the invention the light sensor can be stepwise moved by means of at least one driver relative to the light radiating scene, the immediate position of the light sensor can be recorded by means of at least one position sensor generating output representing said 15 sensor position, said output can be send to a computer having a software program for calculating control values on basis of the received output, and signals representing the calculated control values can be send to the at least one position driver for bringing this to drive the light sensor in such a way that 20 the steps of movement as function of the scannings defines a predetermined curve in a coordinate system.

The predetermined curve can have any appropriate form such as a stairway or be sinusoidal.

25 Another preferred form is a triangle. By choosing a triangle curve the scannings can be performed with equidistant timely distances while the distance between the positions of the light sensor is identical.

30 In practise the light sensor can be movable mounted on a frame and cyclically moved along this by means of the drivers simultaneously with scanning the low resolution first image a number of times by means of an activator bringing the light 35 sensor to scan.

The values calculated after all predetermined number of scannings can advantageously be computed by means of the following formula:

5 $I_z(z) = V_o * A / a(n) - \sum I_a(n) \text{ for } n=1 \text{ to } a=N, n \neq z$ (1)

where

N is the number of subareas that each cell is splitted into,
10 n is the index for subareas in the sensor cell,
a is the area of the n'th subarea of the sensor cell,
V_o is the output signal from the sensor cells,
I_a is the computed light radiation received by the subarea a,
z is the subarea to be calculated,
15 A is the total area of the sensor cell.

This formula is based on the assumption that the output from each imaging surface of the individual sensor cells arranged in a two-dimensional matrix is in principle a representation 20 of the integration of the light intensity on the area of the optical sensor elements:

$$V_o = \int I_a(a) da.$$

25 When there is a definite number of subareas a in A, is the formula:

$$V_o = \sum I_a(n) \text{ for } n=1 \text{ to } N,$$

30 where

N is the number of subareas that each cell is splitted into,
n is the index for subareas in the sensor cell,
V_o is the output signals from the sensor cells,
35 I_a is the computed light radiation received by the subarea a,

The larger the sensor element is the larger will V_o be. It is however necessary that V_o is independent of the area of the sensor, since a given light intensity always must represent the same V_o . Therefore, V_o is scaled in accordance with the 5 pixel area so:

$$V_o = \sum I_a(n) \text{ for } n=1 \text{ to } N, \Rightarrow$$

$$V_o = (1/A) * \sum I_a(n) * a(n) \text{ for } n=1 \text{ to } N,$$

where $a(n)$ is the area of the n 'th subarea.

10 This will of course happen automatically in the sensor via exposure time and related technique in the sensor, but the assumption is important for arriving to formula (1).

15 I_a for a given subarea z is therefore:

$$I_a(z) = V_o * A / a(z) - \sum I_a(n) \text{ for } n=1 \text{ to } n=N, n \neq z \quad (2)$$

where

20 N is the number of subareas that each cell is splitted into,,
 n is the index for subareas in the sensor cell,
 a is the area of the n 'th subarea of the sensor cell,
 V_o is the output signals from the sensor cells,
25 I_a is the computed light radiation received by the subarea a ,
 z is the subarea to be used for calculation,
 A is the area of the sensor cell.

30 If all subareas have equal area, then $A/a(z)=N$ and (1) can be written:

$$I_a(z) = V_o * N - \sum I_a(n) \text{ for } n=1 \text{ to } n=N, a \neq z \quad (3)$$

The formula in (1) can in general work for any subarea in the entire sensor matrix, meaning that the summation of subareas 35 can cover subareas from other sensor cells:

$$I_a(z) = V_o * A/a(z) - \sum I_a(n) \text{ for } n=1 \text{ to } n=N, n \neq z \quad (4)$$

where

5

N is the number of subareas that the summation includes,
n is the index for subareas to be summarised,
a is the area of the n'th subarea,
V_o is the output signal from one of the sensor cells, which
10 includes the subarea a(z),
I_a is the computed light radiation received by the subarea a,
z is the subarea to be used for calculation,
A is the area of the entire subareas.

15 Since the method according to the invention is based on calculated values, or in some instances on estimated values, there will inevitably be generated errors in the calculations.

20 In a preferred embodiment does the method therefore comprise a digital filter for minimising the errors. The digital filter can e.g. use several values from several different set of input values and the set of previous calculated output values to compute a new output value. This will minimise the influence from errors in calculated values or errors in an 25 output value from a sensor cell. Different types of filters can be used, but the most simple type is based on the formula in (2), where each factor on the right side is weighted with a predetermined value.

30 In one embodiment of the invention is it assumed that the light sensor is formed as a X,Y-matrix, with respectively X*Y cells.

35 When the sensor has been moved to a N number of new positions and a N number of sets of output values from the sensor has been stored, a new X_s,Y_r-matrix with X_s*Y_r cells can be

calculated. The new matrix having a row of X^*S cells and a column of T^*Y cells, giving $N \leq S^*T$, and the digital filter as a modification of formula (3) can be written in the form:

5 $I_a(x_s, y_t) = F_v * V_o(x, y) - \sum I_a(x_s-n, y_t-m) * F(x_s-n, y_t-m) \quad (4)$

for $n=1$ to $n=x_s$ and $m=1$ to $m=y_t$; $(n, m) \neq (x_s, y_t)$

where

10 $I_a(x_s, y_s)$ is the light radiation value of the x_s, y_t element in the new X_s, Y_t matrix to be calculated,

$V_o(x, y)$ is the sensor output value from the sensor element in the chosen scanning position covering the (x_s, y_t) subarea,

15 F_v is the predetermined filter coefficient related to the sensor output value from the sensor element in the chosen scanning position covering the (x_s, y_t) subarea,

$I_a(x_s-n, y_t-m)$ is previous calculated I_a values, in the new x_s, y_t matrix,

20 $F(x_s-n, y_s-m)$ is the predetermined filter coefficients related to the previous calculated I_a values for subareas in the new x_s, y_t matrix,

n, m is the number of previous calculated I_a values for subareas in the new x_s, y_s matrix, in the X and Y direction respectively.

25 This digital filter has the advantage that the filter coefficients for previous calculated values of I_a can be smaller and smaller, thereby ensuring that the influence of errors in previous calculated values are minimized.

30 The method can by another advantageously embodiment according to the invention also be carried out in such a way that the scanning and the stepwise movement of the light sensor are asynchronous in relation to each other in the sense that each new scanning is taken place in a sensor position not scanned before whereby an almost infinite high resolution is possible 35 by only scanning a sufficient number of times.

In another embodiment the method can include a calibration procedure. The procedure can consist of steps to move the light sensor to a number of calibration positions by applying known energy values, in terms of current and voltage, to the 5 at least one driver. At each calibration position a signal representing the incident light radiated from the scene can be obtained and a reference value representing the distance moved by the light sensor can be calculated by comparing the different numbers of known energy values with the different 10 signals representing the incident light radiated from the scene.

This calibration procedure can easily and quickly be performed at any time a user wishes or at regular interval of time set 15 by a microprocessor. The procedure further have the advantage that it only uses hardware components already present in the embodiment and does not require additional components, such as movement sensors, which would add to the cost, energy consumption or size of the embodiment.

20 The invention also relates to an apparatus for performing the method according to the invention.

This apparatus correspond in general to the known solid state 25 imaging devices known by the skilled person but with the exception that the optical sensor is arranged in a flexible system comprising means for moving said sensor a predetermined or measurable area which are much less than each of the areas of each sensor element.

30 When the sensor is arranged in a flexible system will the apparatus quickly and accurate be able to make new measurements and output values for each predetermined or measured position.

35

The apparatus can also comprise a computer provided with a software program for establishing a representation of the high resolution image by calculating the representation of the received incident light from the scene at each subarea.

5

The light sensor can preferably be moved by means of an electro-mechanical device or a piezo-element, so that the position of the sensor-matrix can be controlled electrically, and thus the position synchronized to the storing and 10 calculating electronic devices.

A further advantage of the invention, is that each set of output values from the sensor matrix can be transmitted or stored externally together with information about the exact 15 position of the sensor array at the time of the scanning, for calculation in another place or time, for example after transmission through network or storing on digital media. This will give the advantage that no extra computer resources for calculation has to be included in the invented apparatus, but 20 existing resources in the receiving devices can be used.

The invention will be explained in greater detail below, describing only simple idealised exemplary embodiments with reference to the drawing, in which

25

Fig. 1 shows a sensor cell according to the invention with a matrix 16 subareas a in a first and second position,

Fig. 2a-2c is illustrating the method according to the 30 invention in a matrix with one cell-array,

Fig. 3a-3c is illustrating the method according to the invention in a matrix with one cell-array but were there is a physical distance between the cells in the sensor,

35

Fig. 4 is illustrating the method according to the invention in a matrix with one cell-array, but where the influence of an error is minimised by means of a filter according to the invention,

5 Fig. 5 shows schematically an apparatus according to the invention,

10 Fig. 6a-6b shows schematically one embodiment of the invention,

Fig. 7a-7b shows schematically another embodiment of the invention,

15 Fig. 8a-8b shows schematically a third embodiment of the invention,

Fig. 9a-9b shows schematically a fourth embodiment of the invention,

20 Fig. 10a-10c shows a fifth embodiment of the invention in form of a scanner, and

25 Fig. 11 shows schematically a sixth embodiment of the invention.

In fig. 1 is shown a sensor cell 1 with 16 equally sized subareas a moved from a first scanning position 2 to a second scanning position 3.

30 As can be seen there is $T = 6$ overlapping subareas, which means that the total area N of the overlapping subareas is $N=6*a$ while the entire sensor area $A = 16*a$.

35 That means that if the sensor is moved in such a way that the overlapping area only is increasing by the size a of a subarea

during each scanning the resolution can as maximum be extended by the size A.

In fig. 2a is illustrated how the original picture 4, consisting of two black squares 5 and two white squares 6, are being processed by the method according to the invention. The black squares are given the value 0 while the white squares are given the value 256, which are the normal value range used in computer and sensor systems.

The sensor is having a cell-array 7 with 6 cells, and in the next line is seen how the sensor according to the invention is evaluating the image. Each cell is larger than each square in the image. The sensor will therefore not be able to see the correct image resolution. Since each cell only is able to see a number of squares, will each cell give a mean value from the squares. In this case is the first set of squares 5a and 6a and the second set of squares 5b and 6b each given the respective cells mean value of 128 (in the figs. indicated by single-lined right inclined hatching). Therefore, image 8 would be the resulting image in case the image is not further processed.

In fig. 2b is shown how the sensor is making a first scanning 9a, then moving the sensor in the X-direction with a step a, and thereafter making a second scanning 9b.

The incoming output signals from the sensor cells is stored in the electronics attached to the sensor (directly or indirectly) as respectively a first and second set of signals based on each cells incoming light.

The first set of output signal from the sensor is measured as respectively $V_o(1,1)$, $V_o(1,2)$, $V_o(1,3)$, $V_o(1,4)$, $V_o(1,5)$, $V_o(1,6)$, and the second set of output signals are measured as respectively $V_o(2,1)$, $V_o(2,2)$, $V_o(2,3)$, $V_o(2,4)$, $V_o(2,5)$,

$V_o(2,6)$. The o stands for output, s for sensor, the numbers denotes the scan number and the cell number respectively.

The new set of calculated I_a light values are denoted
 5 respectively $I_a(1,1)$, $I_a(2,1)$, $I_a(1,2)$, $I_a(2,2)$, $I_a(1,3)$,
 $I_a(2,3)$, $I_a(1,4)$, $I_a(2,4)$, $I_a(1,5)$ $I_a(2,5)$, $I_a(1,6)$. The numbers
 in the brackets denotes the a value (=1 or 2) and the cell
 number in the original sensor matrix that it originates from,
 respectively.

10

The new picture, which is shown in fig. 2c is now calculated
 by means of the formula (3), as the subareas are equally
 sized.

15 $I_a(z) = V_o * N - \sum I_a(n)$ for $n=1$ to $n=N$, $a \neq z$

where

20 N is the number of subareas that each cell is splitted into,
 n is the index for subareas in the sensor cell,
 a is the area of a subarea of the sensor cell,
 V_o is the output signals from the sensor cells,
 I_a is the computed light radiation received by the subarea a ,
 z is the subarea to be used for calculation,
 25 A is the area of the sensor cell.

The resolution enhancement factor is in the present case 2,
 and for each cell is there a overlapping area T of 1.

30 $I_a(1,1) = V_o(1,1) * 2 - \sum I_a(a)$, in this specific case is $\sum I_a(a)$ not
 known, as no values has been previously calculated, why an
 estimate is given, e.g. the mean value of the starting cell,
 that is $\sum I_a(a) = V_o(1,1)$, therefore:

35 $I_a(1,1) = V_o(1,1) * 2 - V_o(1,1) = 256 * 2 - 256 = 256$
 $I_a(2,1) = V_o(2,1) * 2 - I_a(1,1) = 256 * 2 - 256 = 256$

$$\begin{aligned}
 I_a(1,2) &= V_o(1,2)*2 - I_a(2,1) = 256*2-256=256 \\
 I_a(2,2) &= V_o(2,2)*2 - I_a(1,2) = 128*2-256=0 \\
 I_a(1,3) &= V_o(1,3)*2 - I_a(2,2) = 128*2-0=256 \\
 I_a(2,3) &= V_o(2,3)*2 - I_a(1,3) = 128*2-256=0 \\
 5 \quad I_a(1,4) &= V_o(1,4)*2 - I_a(2,3) = 128*2-0=256 \\
 I_a(2,4) &= V_o(2,4)*2 - I_a(1,4) = 256*2-256=256 \\
 I_a(1,5) &= V_o(1,5)*2 - I_a(2,4) = 256*2-256=256 \\
 I_a(2,5) &= V_o(2,5)*2 - I_a(1,5) = 256*2-256=256 \\
 I_a(1,6) &= V_o(1,6)*2 - I_a(2,5) = 256*2-256=256
 \end{aligned}$$

10 In fig. 3 is shown how the method according to the invention is operation in case each sensor cell is not abutting on the next sensor cell.

15 As can be seen in fig. 3a is the image the same image as in fig. 2a, however the sensor cells 7 are seeing the image differently as there is a space b between the cells. Therefore, image 10 would be the resulting image in case the image is not further processed.

20 In fig. 3b is shown how the space can be covered by three scannings, because the distance between two cells is exactly half the width of a cell. The resulting resolution enhancement will in this case not be equal to N (which is two) as the 25 scannings cover an area which where not covered by the sensor matrix, thereby giving a resolution enhancement of 3.

30 The sensor is making a first scanning 10a, then moving the sensor in the X-direction with a step a, and thereafter making a second scanning 10b, moving the sensor in the X-direction with step a and making a third scanning 10c.

35 The incoming input signals is stored in the sensor electronics attached to the sensor directly or indirectly as respectively a first, a second and a third set of signals based on each cells incoming light.

The first set of output signal from the sensor is measured as respectively $V_o(1,1)$, $V_o(1,2)$, $V_o(1,3)$, $V_o(1,4)$, $V_o(1,5)$, $V_o(1,6)$, and the second set of output signals are measured as 5 respectively $V_o(2,1)$, $V_o(2,2)$, $V_o(2,3)$, $V_o(2,4)$, $V_o(2,5)$, $V_o(2,6)$ and the third set of output signals are measured as respectively $V_o(3,1)$, $V_o(3,2)$, $V_o(3,3)$, $V_o(3,4)$, $V_o(3,5)$, $V_o(3,6)$. The o stands for output, the numbers denotes the scan 10 number and the cell number respectively. A third number would have to be introduced in case of a sensor matrix with more than one row.

The new set of calculated I_a light values are denoted respectively $I_a(1,1)$, $I_a(2,1)$, $I_a(3,1)$, $I_a(1,2)$, $I_a(2,2)$, 15 $I_a(3,2)$, $I_a(1,3)$, $I_a(2,3)$, $I_a(3,3)$, $I_a(1,4)$, $I_a(2,4)$, $I_a(3,4)$, $I_a(1,5)$, $I_a(2,5)$, $I_a(3,5)$, $I_a(1,6)$. The numbers in the brackets denotes the n value (=1, 2 or 3) and the cell number in the original sensor matrix that it originates from, respectively. A third number would have to be introduced in case of a sensor 20 matrix with more than one row.

The new picture, which is shown in fig. 3c is now calculated by means of the formula (3) as the subareas of the sensor cell are equally sized.

25

$$I_a(z) = V_o * N - \sum I_a(n) \text{ for } n=1 \text{ to } n=N, a \neq z$$

where,

30 N is the number of subareas that each cell is splitted into,
 n is the index for subareas in the sensor cell,
 a is the area of a subarea of the sensor cell,,
 V_o is the output signals from the sensor cells,
 I_a is the computed light radiation received by the subarea a ,
35 z is the subarea to be used for calculation,
 A is the area of the sensor cell.

$$\begin{aligned}
 I_a(1,1) &= V_o(1,1)*2 - V_o(1,1) = 256*2-256=256 \text{ (White)} \\
 I_a(2,1) &= V_o(2,1)*2 - I_a(1,1) = 256*2-256=256 \text{ (White)} \\
 I_a(3,1) &= V_o(3,1)*2 - I_a(2,1) = 256*2-256=256 \text{ (White)} \\
 5 \quad I_a(1,2) &= V_o(1,2)*2 - I_a(3,1) = 256*2-256=256 \text{ (White)}
 \end{aligned}$$

Same values until $I_a(1,3)$:

$$I_a(1,3) = V_o(1,3)*2 - I_a(3,2) = 128*2-256=0 \text{ (Black)}$$

$$\begin{aligned}
 10 \quad I_a(2,3) &= V_o(2,3)*2 - I_a(1,3) = 128*2-0= 256 \text{ (White)} \\
 I_a(3,3) &= V_o(3,3)*2 - I_a(2,3) = 128*2-256=0 \text{ (Black)} \\
 I_a(1,4) &= V_o(1,4)*2 - I_a(3,3) = 128*2-0= 256 \text{ (White)} \\
 I_a(2,4) &= V_o(2,4)*2 - I_a(1,4) = 256*2-256=256 \text{ (White)} \\
 I_a(3,4) &= V_o(3,4)*2 - I_a(2,4) = 256*2-256=256 \text{ (White)}
 \end{aligned}$$

15 .

$$I_a(3,5) = V_o(3,5)*2 - I_a(2,5) = 256*2-256=256 \text{ (White)}$$

20 In both cases is made an estimate of the initial value of $I_a(1,1)$. In case this estimate is wrong or contains an error will the mistake propagate throughout the calculations.

In fig. 4 is shown how one embodiment of the digital filter according to the invention is used for correcting an error.

25 The original picture 11 in (4) has a grey background (in the figs. indicated by single-lined right inclined hatching) with value 128 and two grey dots (12a,12b) with value 64 (in the figs. indicated by small cross-hatching). With one scan 13 the 30 resulting picture would be 14. According to the invention two scans 15a,15b are used in this example to double the resolution, $A=2$. The sensor cells measure the grey background correctly with values 128, but the output $V_o(2,2)$ (output from scan 2, sensor cell 2) is due to a distortion or other error, 35 measured as 80 instead of 96, which would be the correct value. This will cause all the calculated new values after

$I_a(1,2)$ to be incorrect 16, which can be seen by the following calculation:

5 $I_a(1,1) = V_o(1,1) * 2 - V_o(1,1) = 128 * 2 - 128 = 128$ (Estimated initial value)
 10 $I_a(2,1) = V_o(2,1) * 2 - I_a(1,1) = 128 * 2 - 128 = 128$
 15 $I_a(1,2) = V_o(1,2) * 2 - I_a(2,1) = 128 * 2 - 128 = 128$
 20 $I_a(2,2) = V_o(2,2) * 2 - I_a(1,2) = 80 * 2 - 128 = 32$
 25 $I_a(1,3) = V_o(1,3) * 2 - I_a(2,2) = 96 * 2 - 32 = 160$
 30 $I_a(2,3) = V_o(2,3) * 2 - I_a(1,3) = 96 * 2 - 160 = 32$
 35 $I_a(1,4) = V_o(1,4) * 2 - I_a(2,3) = 96 * 2 - 32 = 160$
 40 $I_a(2,4) = V_o(2,4) * 2 - I_a(1,4) = 128 * 2 - 160 = 96$
 45 $I_a(1,5) = V_o(1,5) * 2 - I_a(2,4) = 96 * 2 - 32 = 160$
 50 $I_a(2,5) = V_o(2,5) * 2 - I_a(1,5) = 128 * 2 - 160 = 96$
 55 $I_a(1,6) = V_o(1,6) * 2 - I_a(2,5) = 96 * 2 - 32 = 160$

It is obvious that the error introduced in $V_o(2,2)$ will influence on all the following calculations, and will cause an oscillation even when V_o has stopped changing. This is shown in 20 the resulting picture 16a.

In the calculations of the I_a values in 16b a very simple digital filter according to (4) has been introduced. This 25 digital filter has the advantage that it can use more values from previous measured and/or calculated cells to calculate new I_a values, thereby minimising the influence of noise and other errors:

30 The filter coefficients are chosen to:

35 $F_o = 2$
 40 $F(-1,0) = 0.75$
 45 $F(-2,0) = 0.25$ (only one row in the sensor matrix)
 50 All other coefficients in (4) are set to 0.

55 $I_a(1,1) = V_o(1,1) * 2 - V_o(1,1)$

```

          = 128*2-128
          = 128 (Estimated initial value)
Ia(2,1) = Vo(2,1)*2-0.75*Ia(1,1)-0.25*Ia(1,1)
          = 2*128-0.75*128+0.25*128
5          = 128
(Ia(1,1) are used two times, as no present value exist)
Ia(1,2) = Vo(1,2)*2-0.75*Ia(2,1)-0.25*Ia(1,1)
          = 2*128-0.75*128+0.25*128
          = 128
10 Ia(2,2) = Vo(2,2)*2-0.75*Ia(1,2)-0.25*Ia(2,1)
          = 2*80-0.75*128+0.25*128
          = 32
Ia(1,3) = Vo(1,3)*2-0.75*Ia(2,2)-0.25*Ia(1,2)
          = 2*96-0.75*32+0.25*128
15          = 136
Ia(2,3) = Vo(2,3)*2-0.75*Ia(1,3)-0.25*Ia(2,2)
          = 2*96-0.75*136+0.25*32
          = 82
Ia(1,4) = Vo(1,4)*2-0.75*Ia(2,3)-0.25*Ia(1,3)
20          = 2*96-0.75*82+0.25*136
          = 96.5
Ia(2,4) = Vo(2,4)*2-0.75*Ia(1,4)-0.25*Ia(2,3)
          = 2*128-0.75*96.5+0.25*82
          = 163
25 Ia(1,5) = Vo(1,5)*2-0.75*Ia(2,4)-0.25*Ia(1,4)
          = 2*128-0.75*163+0.25*96.5
          = 109.5
Ia(2,5) = Vo(2,5)*2-0.75*Ia(1,5)-0.25*Ia(2,4)
          = 2*128-0.75*109.5+0.25*163
30          = 133
Ia(1,6) = Vo(1,6)*2-0.75*Ia(2,5)-0.25*Ia(1,5)
          = 2*128-0.75*109.5+0.25*163
          = 129

```

In fig. 4 the different values in accordance with the calculation above are indicated by means of different types of hatching.

5 As can be seen from this example, the error introduced in the measurement of cell $V_{(2,2)}$ will not cause oscillations in the following calculations and the influence will disappear. The resulting picture can be seen in 16b.

10 Fig. 5 illustrates in form of an apparatus 17 by way of example the basic principle for using the invention in a web camera.

15 The apparatus 17 comprises a light sensor 18 with a number of cells 19 formed as a matrix. The sensor serves for receiving incident light radiated from a scene (not shown). The light sensor is movable mounted on a frame 20. Two drivers 21 are furthermore arranged for cyclically moving the light sensor along the frame in a X and Y direction.

20 The drivers could e.g. be a piezo-element or an electro-mechanical device.

25 Each driver is associated with a position sensor 22 for recording the immediate position of the light sensor relative to the frame and for generating output representing said position.

30 A computer 23 serves for receiving the generated output from the position sensors and for, by means of a software program, calculating control values which via a circuit 24 is send to the two position drivers 21 for bringing these to drive the light sensor 18 in such a way that the steps of movement as function of the scannings defines a predetermined curve in a 35 coordinate system.

The apparatus functions in principle in the way described above with reference to the figures 1 - 16.

More specific, the light sensor 18 is by means of an activator (not shown) cyclically brought to scan the scene (not shown) a number of times.

Simultaneously with the scanning the light sensor is stepwise moved an identical number of times along the frame in the X-Y direction while defining a number of subareas, whereby the total distance covered during said movements of the light sensor corresponds to the extend of the cell and the distance to the next cell in the X-Y direction, respectively.

15 During said operation of the apparatus output representing the received incident light from the scene at each sensor cell is send from the light sensor 18 to the computer 23 via another circuit 25, which is shown in bold line.

20 By storing the received output from the light sensor and adding information about the position of the sensor at the time of scanning by means of another software program, the computer can transmit the pictures and added information to another computer (not shown) by means of the circuit 26 which can be any kind of wired or wireless connection or network. The receiving computer at the other end of the network can then establish a representation of the high resolution picture by calculating the representation of the received incident light from the scene at each subarea.

30 The adding of information about the position together with the images, can be done in several ways. However, to avoid destroying the information when converting images from one file format to another, the information about the position of the sensor 18 at the time of scanning of the scene (not shown) is coded directly into the image by means of a software

program in the embedded computer 25. The program advantageously uses some of the pixels in the scanned image and substitutes these with information about the position. The missing pixels will at the time of displaying be substituted with picture information by means of another software program. This can be done by means of different known interpolating software algorithms known by persons skilled in image processing.

10 By this method, the information about the position of the sensor 18 will be consistent in the picture, even if transformation to other file formats takes place before the calculation of high-resolution pictures.

15 The calculated representation of the high resolution picture can then be shown on different kind of displaying devices as computer screens and projectors.

20 The above mentioned curve which is showing the steps of movement as function of the scannings in a coordinate system can within the scope of the invention in itself have any suitable form. In the following advantages and drawbacks of some representative curves are mentioned.

25 In fig. 6a and 6b is illustrated a simple principle for moving a light sensor 26, which in this case is only moved in the Y-direction. It is, however, obvious that the movement as well could be in the X-direction.

30 Fig 6b shows a coordinate system where the time of scanning is shown on the axis of abscissas and the position of the light sensor on the axis of ordinate.

35 The scannings are performed with equidistant time intervals and the distance between each position of the light sensor 26 is identical to these intervals. Thereby the movement of the

light sensor as function of the scannings needs to precisely follow a triangle curve as shown in fig. 6b.

5 Fig. 7a illustrates a sensor matrix 27 moved in the diagonal direction, which is simple to control merely mechanical since the movements only take place in one direction.

10 The subsequent calculations are, on the other hand, relatively complicated as the subareas are having different sizes, which need to be converted by means of interpolation to equal quadratic pixels elements before being able to show the high resolution picture on e.g. a television screen.

15 As shown in fig. 7b are the scanning positions asynchronous with scanning times. That means that each new scanning is taken place in a matrix position not scanned before whereby an almost infinite high resolution is possible by only scanning a sufficient number of times.

20 20 The distances between the positions of the sensor matrix and the scanning times, respectively, are as in the example shown in fig 6a and 6b equidistant thereby requiring that the curve shown in fig. 7b must be a triangle.

25 25 In fig. 8a the sensor matrix 28 is carrying out free oscillations which is the most simple way for mechanically moving the sensor. The oscillations shall, however, still be controlled in such a way that they are kept within the wanted limitations.

30

Fig. 8b shows a situation where the distance between the scannings is equal in time whereby the distances between the positions of the sensor matrix 28 will be different resulting in complicated subsequent calculations and reduced precision 35 of this calculations.

Fig. 9a and 9b show the same as in fig. 8a and 8b. The only difference is that the distances between the positions of the sensor matrix now are constant whereas the distance in time between the scannings is varying. This mode of using the invention requires in many cases a picture buffer as most receivers, such as computers or servers or the like will require that the pictures arrives with equal distances in time.

Fig. 10a, 10b and 10c illustrate the invention used in a scanner.

In a scanner a sensor matrix having three arrays usually is used. Each array having a red (R), green (G) or blue (B) filter. All colours are scanned in one scan (single pass) while a step motor is moving the three arrays over the object to be scanned.

Some scanners are using only one array. In this case will the filter be changed between each scan, i. e. that the array shall pass the object three times, (multipass).

The resolution in a scanner is depending on the number of elements in the array and of the possible precision of the movement of the arrays. Typically will the resolution in the movement direction of the array be the double of the resolution in the direction of the array itself, conventionally 300x600 dpi or 600x1200 dpi. The distances between each pixel cause this, which typically is in the same order of magnitude as the pixel itself, whereby a higher resolution is possible in the Y-direction where the step motors can move in steps of precisely one pixel.

By using the invention in a scanner the size of the pixel will not any more be the restricting factor as the array can be

moved in the X-direction by means of an arrangement similar to the arrangement shown in fig. 6a.

5 The movement in the Y-direction can be carried out by means of a step motor, but in even smaller steps independent of the size of the pixels whereby the wanted resolution can be obtained.

10 This arrangement is shown in fig. 10 showing a scanner 29 having three arrays 30, 31 and 32 of cells R (red), G (green) and B (blue).

15 One driver 33 are arranged for cyclically moving the arrays in the X-direction.

20 The driver is associated with a position sensor 34 for recording the immediate position of the light sensor in the X-direction and for generating output representing said position.

25 A computer 35 serves for receiving the generated output from the position sensors and for, by means of a software program, calculating control values which via a circuit 36 is send to the position driver 33 for bringing this to drive the three arrays cyclically in a wanted mode along the X-axis as illustrated in fig. 10b, while the three arrays is moved along the Y-axes by means of a stepmotor as illustrated in fig. 10c.

30 Fig.11 shows another advantageous embodiment of the apparatus according to the invention. The apparatus comprise a light sensor 18 with a number of cells 19 formed as a matrix. The sensor serves for receiving light radiated from a scene (not shown). The light sensor is mounted on a sensor frame 20, such as a printed circuit board or similar. The frame is further 35 movably mounted on a base frame 37, such as a circuit board or

similar, by means of a resilient mountings 38, such as rubber suspensions, springs or the like.

Two drivers implemented as coils 39, which are rigidly mounted
5 on the base frame, and corresponding anchoring means 40, and
for example consist of a ferromagnetic material, which is
mounted on the sensor frame, which sensor frame is moveable
mounted on the base frame. When applying electrical energy, in
terms of current and voltage, to these coils 39 a magnetic
10 field will be induced, which will attract the anchors 40
mounted on the sensor frame, thereby moving the sensor frame
in the x respective y direction, where the distance moved will
be dependent on the amount of electrical energy applied to the
individual coil 39.

15 An embedded computer 23 serves for, by means of a software
program to calculate control values in terms of current and
voltages which via a third circuit 41 is sent to the two coils
39 bringing these to move the light sensor 18 mounted on the
20 sensor frame 37 in steps, where a predetermined curve in a
coordinate system is defined by the steps as a function of the
scanning.

25 The steps is measured with a precision of microns, it is
therefore necessary to be able to move the sensor very
precisely in fractions of the size of the individual sensor
elements, or to obtain precise information about the position
of the sensor. In the present invention the precise movement
30 of the apparatus is achieved by measuring the position of the
sensor frame 20 and thereby the sensor 18 at different
predetermined sets of the applied values of current and
voltage. This is usually only done once in a calibration
procedure as follows:

35 The embedded computer 23 applies a number of known values of
energy, in terms of current and voltage to the coils 39, which

will move the sensor frame in an equal number of displacement positions.

5 For each applied value of energy the displacement of the sensor frame is compared to a reference position, which is the position of the sensor frame where no energy is applied. Each value of energy is measured and stored in the embedded computer 23.

10 The measurement of the displacement is done by means of the sensor 18. For each new value of energy applied to the coils, a signal representing the scene (not shown) obtained by the sensor 18 is sent to the embedded computer 23 through a fourth circuit 42.

15 The embedded computer stores every representation of the scene and the matching energy value. Alternatively the embedded computer sends the representation and matching energy values to be stored in an external computer 43, which is connected to 20 the embedded computer 23 through any kind of network 44.

25 By means of a software program the embedded computer 23 or the external computer 43 analyses and compare the different representations of the scene obtained by the sensor 18 in the different positions. The program then calculate how many pixels the sensor frame 20 have moved by comparing different values of applied energy to the coils 39 with the different signals representing the scene (not shown), thus finding the displacement of the sensor frame 20 and the sensor 18, thereby 30 enabling the embedded computer 23 to move the sensor frame 20 and thereby the sensor 18 any predetermined distance after the calibration procedure has taken place. Normally this calibration procedure only needs to take place once.

Claims

1. A method for converting a low resolution first image produced by means of a light sensor (18;19) for receiving 5 incident light radiated from a scene to a high resolution second image, whereby said light sensor is constructed as an array (30;31;32) or a matrix (27;28) having a number of cells (1;19), each defining a predetermined area, comprising

- that said first image is cyclically scanned a number 10 of times,
- that the light sensor simultaneously with the scanning stepwise is moved an identical number of times relative to the light radiating scene in at least one direction thereby defining a number of subareas,
- that the total distance covered during movement of the light sensor corresponds to the extend of the cell or to to the extend of the cell plus a distance defined by or to the neighbour cell in said at least one direction, and
- that a representation of the high-resolution second image 20 is established by calculating the representation of the received incident light from the scene at each subarea.

2. A method according to claim 1, comprising that the light sensor (18;19) for each step is moved a distance 25 corresponding to the extend of the area covered by the cell in the direction of movement or to the extend of the area covered by the cell in the direction of movement plus a distance defined by or to the neighbour cell in the direction of movement divided with the number of scanning times.

3. A method according to claim 1, comprising that the light sensor (18;19) for each step is moved a distance 35 corresponding to the extend of the area covered by the cell plus a distance defined by or to the neighbour cell minus the extend of the area of the smallest subarea to be

calculated in the direction of movement, divided with the number of scanning times.

4. A method according to claim 1, comprising that the light sensor (18;19) is moved asynchronous to the scannings.
- 5
- 10
5. A method according to claim 1, comprising that the received incident light from the scene is represented as a number of pixels at each subarea, substituting at least some of the pixels with information of the position of the sensor frame (20) and thereby providing an identifiable coding of the position of the sensor frame (20) into the low resolution first image.
- 15
6. A method according to each of the claims 1 - 5, comprising that the high resolution second image is computed by calculating the value for each subarea by means of the formula:

$$20 \quad I_a(z) = V_o * A/a(z) - \sum I_a(n) \text{ for } n=1 \text{ to } n=N, n \neq z$$

where

N = the number of subareas that each cell is splitted into,
25 n = the index for subareas in the sensor cell,
a = the area of a subarea of the sensor cell,
V_o = the output signals from the sensor cells,
I_a = the computed light radiation received by the subarea a,
z = the subarea to be used for calculation,
30 A = the area of the sensor cell.

7. A method according to each of the claims 1 - 6, comprising
 - stepwise moving the light sensor by means of at least one driver relative to the light radiating scene,

- recording the immediate position of the light sensor by means of at least one position sensor generating output representing said sensor position,
- sending said output to a computer having a software program for calculating control values on basis of the received output, and
- sending signals representing the calculated control values to the at least one position driver for bringing this to drive the light sensor in such a way that the steps of movement as function of the scannings defines a predetermined curve.

10 8. Method according to claim 7, comprising a calibration procedure consisting of steps to,

- moving the light sensor to a number of calibration positions by applying known energy values to the at least one driver,
- at each calibration position obtaining a signal representing the incident light radiated from the scene, and
- calculating a reference value representing the distance of the movement of the light sensor by comparing the different numbers of known energy values with the different signals representing the incident light radiated from the scene.

20 9. An apparatus according to claims 7 or 8, wherein the at least one driver (21;33) comprise a coil (39) rigidly mounted on a base frame (37) and an anchoring means (40) mounted on the sensor frame (20), said sensor frame being moveable mounted on the base frame, and said anchoring means to be actuated by an attractive force induced by the coil and thereby pulling the anchor toward the coil.

35 10. A method according to claims 7, 8 or 9, comprising that the predetermined curve describing the steps of movement as

function of the scannings in a coordinate system is formed as triangle or a stairway or is sinusoidal.

11. A method according to each of the claims 1 - 10,
5 comprising that the light sensor (18;19) is moved by means of a piezoelectric-element or an electro-mechanical device.
12. A method according to each of the claims 1 - 10,
10 comprising that the scene is moved relative to the light sensor (18;19) by means of a piezo-element or an electro-mechanical device.
13. A method according to each of the claims 1 - 12,
15 comprising that the light sensor (18;19) is moved in a system of x-y coordinates and moved at least in one of the x-y directions of this system or in the direction of a cell of the light sensor.
14. A method according to each of the claims 1 - 13,
20 comprising that the method further comprises a step for minimising the influence of errors in previous calculated or estimated values.
15. A method according to each of the claims 1 - 14,
25 comprising that the influence of errors in previous calculated or estimated values is minimised by means of a digital filter.
16. A method according to claim 15, comprising that the digital filter is using several values from several cycles to compute a filter output value by the following formula

$$\begin{aligned} I_a(nX_A, mY_A) = & (F_{1,1}) * V_0(p_{(1)}X, q_{(1)}Y) - (F_{2,2}) * V_0(p_{(2)}X, q_{(2)}Y) - (F_{3,3}) * \\ & \dots - (F_{A,A}) * V_0(p_{(A)}X, q_{(A)}Y) - (G_{-1,-0}) * I_a(n_{-1}X_A, m_{-0}Y_A) - (G_{-0,-1}) \\ 35 & * I_a(n_0X_A, m_{-1}Y_A) - (G_{-1,-1}) * I_a(n_{-1}X_A, m_{-1}Y_A) \\ & \dots - (G_{-n,-m}) * I_a(n_{-n}X_A, m_{-m}Y_A), \end{aligned}$$

where,

- $I_a(nX_a, mY_a)$ is the light radiation value of the n, m 'th element in the new X_a, Y_a matrix to be calculated,
- $I_a(n_{-1}X_a, m_0Y_a)$ is the previous calculated element of the $n-1, m$ 'th element of the new X_a, Y_a matrix,
- $(G_{-1,-0})$ is the belonging predetermined filter value,
- $I_a(n_0X_a, m_{-1}Y_a)$ is the previous calculated element of the $n, m-1$ 'th element of the new X_a, Y_a matrix,
- $(G_{0,-1})$ is the belonging predetermined filter value,
- $I_a(n_{-n}X_a, m_{-m}Y_a)$ is the previous calculated element of the $n-n, m-m$ 'th element of the new X_a, Y_a matrix,
- $(G_{-n,-m})$ is the belonging predetermined filter value,
- $V_o(p_{(1)}X, q_{(1)}Y)$ is the measured and stored output value of the p, q 'th element in the physical sensor matrix overlapping the n, m 'th element in the new calculated X_a, Y_a matrix from the first position,
- $(F_{1,1})$ is the belonging predetermined filter value,
- p, q are calculated from n/A and m/A ,
- $V_o(p_{(A)}X, q_{(A)}Y)$ is the measured and stored output value of the p, q 'th element in the physical sensor matrix overlapping the n, m 'th element in the new calculated X_a, Y_a matrix from the A 'th position,
- $(F_{A,A})$ is the belonging predetermined filter value, and p, q are calculated from n/A and m/A .

17. An apparatus (17) for converting a low resolution first image to a high resolution second image, comprising
 - a light sensor (18) for receiving incident light radiated from a scene to a high resolution second image, whereby said light sensor is constructed as an array (30;31;32) or a matrix (27;28) having a number of cells (1;19), each defining a predetermined area,

- means for bringing the apparatus cyclically to scan the first image a number of times by means of the light sensor,
- means (21;33;39,40) for simultaneously with the scanning stepwise to move the light sensor an identical number of times relative to the light radiating scene in at least one direction, whereby the total distance covered during said movement of the light sensor corresponds to the extend of the cell or to the extend of the cell plus a distance defined by or to the neighbour cell in said at least one direction and a number of subareas are defined, and
- means (23;35) for establishing a representation of the high resolution second image by calculating the representation of the received incident light from the scene at each subarea.

18. An apparatus for converting a low resolution first image to a high resolution second image, comprising,

- a light sensor (1;19) for receiving incident light radiated from a scene to a high resolution second image, whereby said light sensor is constructed as an array (30;31;32) or a matrix (27;28) having a number of cells, each defining a predetermined area,
- a frame for movable mounting said light sensor,
- an activator for bringing the apparatus cyclically to scan the low resolution first image a number of times by means of said light sensor,
- at least one driver (21;33;39,40) for simultaneously with the scanning stepwise to move the light sensor an identical number of times relative to the light radiating scene in at least one direction, whereby the total distance covered during said movement of the light sensor corresponds to the extend of the cell or to the extend of the cell plus a distance defined by or to the neighbour

cell in said at least one direction and a number of subareas are defined, and

- at least one position sensor for recording the immediate position of the light sensor relative to the frame and sending output representing said position to a computer having a software program for calculating control values on basis of the received output and sending signals representing the calculated control values to the at least one position driver for bringing this to drive the light sensor in such a way that the steps of movement as function of the scannings defines a predetermined curve in a coordinate system.

19. An apparatus according to claim 17 or 18, comprising that a representation of the high resolution second image is established by calculating the representation of the received incident light from the scene at each subarea by means of the formula:

$$I_a(z) = V_o * A / a(z) - \sum I_a(n) \text{ for } n=1 \text{ to } n=N, n \neq z$$

where

N = the number of subareas that each cell is splitted into,
25 n = the index for subareas in the light sensor cell,
a = the area of a subarea of the light sensor cell,
V_o = the output signals from the light sensor cells,
I_a = the computed light radiation received by the subarea a,
z = the subarea to be used for calculation,
30 A = the area of the light sensor cell.

20. An apparatus according to claim 17 or 18, comprising that the apparatus further comprises a digital filter arranged for minimising the influence of at least one error in the value.

21. An apparatus according to claim 17 or 18, comprising that the digital filter are using several values from several cycles to compute a filter output value by the following formula

5

$$\begin{aligned}
 I_a(nX_A, mY_A) = & (F_{1,1}) * V_0(p_{(1)}X, q_{(1)}Y) - (F_{2,2}) * V_0(p_{(2)}X, q_{(2)}Y) - (F_{3,3}) * \\
 & \dots - (F_{A,A}) * V_0(p_{(A)}X, q_{(A)}Y) - (G_{-1,-0}) * I_a(n_{-1}X_A, m_{-0}Y_A) - (G_{-0,-1}) * \\
 & * I_a(n_{-0}X_A, m_{-1}Y_A) - (G_{-1,-1}) * I_a(n_{-1}X_A, m_{-1}Y_A) \\
 & \dots - (G_{-n,-m}) * I_a(n_{-n}X_A, m_{-m}Y_A),
 \end{aligned}$$

10

where,

- $I_a(nX_A, mY_A)$ is the light radiation value of the n, m 'th element in the new X_A, Y_A matrix to be calculated,
- 15 - $I_a(n_{-1}X_A, m_{-0}Y_A)$ is the previous calculated element of the $n-1, m$ 'th element of the new X_A, Y_A matrix,
- $(G_{-1,-0})$ is the belonging predetermined filter value,
- $I_a(n_{-0}X_A, m_{-1}Y_A)$ is the previous calculated element of the $n, m-1$ 'th element of the new X_A, Y_A matrix,
- 20 - $(G_{-0,-1})$ is the belonging predetermined filter value,
- $I_a(n_{-n}X_A, m_{-m}Y_A)$ is the previous calculated element of the $n-n, m-m$ 'th element of the new X_A, Y_A matrix, $(G_{-n,-m})$ is the belonging predetermined filter value,
- 25 - $V_0(p_{(1)}X, q_{(1)}Y)$ is the measured and stored output value of the p, q 'th element in the physical sensor matrix overlapping the n, m 'th element in the new calculated X_A, Y_A matrix from the first position,
- $(F_{1,1})$ is the belonging predetermined filter value,
- p, q are calculated from n/A and m/A ,
- 30 - $V_0(p_{(A)}X, q_{(A)}Y)$ is the measured and stored output value of the p, q 'th element in the physical sensor matrix overlapping the n, m 'th element in the new calculated X_A, Y_A matrix from the A 'th position,
- $(F_{A,A})$ is the belonging predetermined filter value, and p, q are calculated from n/A and m/A .

22. An apparatus according to claim 17 or 18, comprising that the computer (23;35) is provided with a software program for establishing a representation of the high resolution image by calculating the representation of the received incident light from the scene at each subarea.

5

23. An apparatus according to claim 17 or 18, comprising that the predetermined curve is formed as a triangle or a stairway or is sinusoidal.

10

24. An apparatus according to claim 17 or 18, comprising that the light sensor (1;19) is moved in system of x-y co-ordinates and moved at least in one of the x-y directions.

15

25. An apparatus according to each of the claim 17 or 18, comprising that the at least one driver (21;33;39,40) is an electro-mechanical device or a piezoelectric-element.

20 26. A use of the method according to claims 1 - 25 and the apparatus according to claims 17 - 24 in a web camera or a still picture camera or camcorder or a monitoring camera or a 360° camera or a digital binocular glasses or a scanner.

AMENDED CLAIMS

[received by the International Bureau on 07 January 2003 (07.01.03);
original claims 1-26 replaced by new claims 1-29]

1. A method for converting a low resolution first image produced by means of a light sensor (18) for receiving incident light radiated from a scene to a high resolution second image, whereby said light sensor is constructed as an array (30;31;32) or a matrix (27;28) having a number of cells (1;19), each defining a predetermined area, comprising
 - that said first image is cyclically scanned a number of times,
 - that the light sensor simultaneously with the scanning stepwise is moved an identical number of times relative to the light radiating scene in at least one direction thereby defining a number of subareas,
 - that the total distance covered during movement of the light sensor corresponds to the extend of the cell or to the extend of the cell plus a distance defined by or to the neighbour cell in said at least one direction, and
 - that a representation of the high-resolution second image is established by calculating the representation of the received incident light from the scene at each subarea.
2. A method according to claim 1, comprising that the light sensor (18) for each step is moved a distance corresponding to the extend of the area covered by the cell in the direction of movement or to the extend of the area covered by the cell in the direction of movement plus a distance defined by or to the neighbour cell in the direction of movement divided with the number of scanning times.
3. A method according to claim 1, comprising that the light sensor (18) for each step is moved a distance corresponding to the extend of the area covered by the cell plus a distance defined by or to the neighbour cell minus the extend of the area of the smallest subarea to be

calculated in the direction of movement, divided with the number of scanning times.

4. A method according to claim 1, comprising that the light sensor (18) is moved asynchronous to the scannings.

5. A method according to claims 1 - 4, comprising that the received incident light from the scene is represented as a number of pixels at each subarea, substituting at least some 10 of the pixels with information of the position of the light sensor (18) mounted on a sensor frame (20) and thereby providing an identifiable coding of the position of the light sensor (18) mounted on the sensor frame (20) into the low resolution first image.

15 6. A method according to each of the claims 1 - 4, comprising that the high resolution second image is computed by calculating the value for each subarea by means of the formula:

$$I_a(z) = V_o * A/a(z) - \sum I_a(n) \text{ for } n=1 \text{ to } n=N, n \neq z$$

where

25 N = the number of subareas that each cell is splitted into,

n = the index for subareas in the sensor cell,

a = the area of a subarea of the sensor cell,

V_o = the output signals from the sensor cells,

I_a = the computed light radiation received by the subarea a,

30 z = the subarea to be used for calculation,

A = the area of the sensor cell.

7. A method according to each of the claims 1 - 5, comprising

- stepwise moving the light sensor by means of at least one driver relative to the light radiating scene,

- recording the immediate position of the light sensor (18) by means of at least one position sensor generating output representing said sensor position,
- sending said output to a computer having a software program for calculating control values on basis of the received output, and
- sending signals representing the calculated control values to the at least one position driver for bringing this to drive the light sensor (18) in such a way that the steps of movement as function of the scannings defines a predetermined curve.

8. Method according to claim 6, comprising a calibration procedure consisting of the steps of,

- moving the light sensor (18) to a number of calibration positions by applying known energy values to the at least one driver,
- at each calibration position obtaining a signal representing the incident light radiated from the scene, and
- calculating a reference value representing the distance of the movement of the light sensor (18) by comparing the different numbers of known energy values with the different signals representing the incident light radiated from the scene.

9. A method according to claims 6 or 7, comprising that the predetermined curve describing the steps of movement as function of the scannings in a coordinate system is formed as triangle or a stairway or is sinusoidal.

10. A method according to each of the claims 1 - 8, comprising that the light sensor (18) is moved by means of a piezoelectric-element or an electro-mechanical device.

11. A method according to each of the claims 1 - 8, comprising that the scene is moved relative to the light sensor (18) by means of a piezo-element or an electro-mechanical device.

5 12. A method according to each of the claims 1 - 10, further comprising the steps of

- moving the light sensor (18) by means of a coil (39) rigidly mounted on a base frame (37) and an anchoring means (40) mounted on a sensor frame (20), said sensor frame being moveable mounted on the base frame, and
- actuating said anchoring means by an attractive force induced by the coil, and thereby pulling the anchor toward the coil

15 13. A method according to each of the claims 1 - 11, comprising that the light sensor (18) is moved in a system of x-y coordinates and moved at least in one of the x-y directions of this system or in the direction of a cell of the light sensor (18).

20 14. A method according to each of the claims 1 - 12, comprising that the method further comprises a step for minimising the influence of errors in previous calculated or estimated values.

25 15. A method according to each of the claims 1 - 13, comprising that the influence of errors in previous calculated or estimated values is minimised by means of a digital filter.

30 16. A method according to claim 14, comprising that the digital filter is using several values from several cycles to compute a filter output value by the following formula

$$35 I_a(nX_a, mY_a) = (F_{1,1}) * V_0(p_{(1)}X, q_{(1)}Y) - (F_{2,2}) * V_0(p_{(2)}X, q_{(2)}Y) - (F_{3,3}) * \dots - (F_{k,k}) * V_0(p_{(k)}X, q_{(k)}Y) - (G_{-1,-1}) * I_a(n_{-1}X_a, m_{-1}Y_a) - (G_{-0,-0})$$

$*I_a(n_0X_A, m_1Y_A) - (G_{-1,-1}) *I_a(n_{-1}X_A, m_{-1}Y_A)$
 $\dots - (G_{-n,-m}) *I_a(n_{-n}X_A, m_{-m}Y_A),$

where,

5

- $I_a(nX_A, mY_A)$ is the light radiation value of the n, m 'th element in the new X_A, Y_A matrix to be calculated,
- $I_a(n_{-1}X_A, m_0Y_A)$ is the previous calculated element of the $n-1, m$ 'th element of the new X_A, Y_A matrix,
- 10 - $(G_{-1,-0})$ is the belonging predetermined filter value,
- $I_a(n_{-0}X_A, m_1Y_A)$ is the previous calculated element of the $n, m-1$ 'th element of the new X_A, Y_A matrix,
- $(G_{-0,-1})$ is the belonging predetermined filter value,
- 15 - $I_a(n_{-n}X_A, m_{-m}Y_A)$ is the previous calculated element of the $n-n, m-m$ 'th element of the new X_A, Y_A matrix,
- $(G_{-n,-m})$ is the belonging predetermined filter value,
- $V_0(p_{(1)}X, q_{(1)}Y)$ is the measured and stored output value of the p, q 'th element in the physical sensor matrix overlapping the n, m 'th element in the new calculated X_A, Y_A matrix from the first position,
- 20 - $(F_{1,1})$ is the belonging predetermined filter value,
- p, q are calculated from n/A and m/A ,
- $V_0(p_{(A)}X, q_{(A)}Y)$ is the measured and stored output value of the p, q 'th element in the physical sensor matrix overlapping the n, m 'th element in the new calculated X_A, Y_A matrix from the A 'th position,
- 25 - $(F_{A,A})$ is the belonging predetermined filter value, and p, q are calculated from n/A and m/A .

30

17. An apparatus (17) for converting a low resolution first image to a high resolution second image, comprising

- a light sensor (18) for receiving incident light radiated from a scene to a high resolution second image, whereby said light sensor (18) is constructed as an array

35

(30;31;32) or a matrix (27;28) having a number of cells (1;19), each defining a predetermined area,

- means for bringing the apparatus cyclically to scan the first image a number of times by means of the light sensor (18),
- means (21;33;39,40) for simultaneously with the scanning stepwise to move the light sensor (18) an identical number of times relative to the light radiating scene in at least one direction, whereby the total distance covered during said movement of the light sensor (18) corresponds to the extend of the cell or to the extend of the cell plus a distance defined by or to the neighbour cell in said at least one direction and a number of subareas are defined, and
- means (23;35) for establishing a representation of the high resolution second image by calculating the representation of the received incident light from the scene at each subarea.

20 18. An apparatus for converting a low resolution first image to a high resolution second image, comprising,

- a light sensor (1;19) for receiving incident light radiated from a scene to a high resolution second image, whereby said light sensor (18) is constructed as an array (30;31;32) or a matrix (27;28) having a number of cells, each defining a predetermined area,
- a frame for movable mounting said light sensor (18),
- an activator for bringing the apparatus cyclically to scan the low resolution first image a number of times by means of said light sensor,
- at least one driver (21;33;39,40) for simultaneously with the scanning stepwise to move the light sensor an identical number of times relative to the light radiating scene in at least one direction, whereby the total distance covered during said movement of the light sensor corresponds to the extend of the cell or to the extend of

the cell plus a distance defined by or to the neighbour cell in said at least one direction and a number of subareas are defined, and

- at least one position sensor for recording the immediate position of the light sensor relative to the frame and sending output representing said position to a computer having a software program for calculating control values on basis of the received output and sending signals representing the calculated control values to the at least one position driver for bringing this to drive the light sensor in such a way that the steps of movement as function of the scannings defines a predetermined curve in a coordinate system.

15 19. An apparatus according to claim 17 or 18, comprising that a representation of the high resolution second image is established by calculating the representation of the received incident light from the scene at each subarea by means of the formula:

20

$$I_a(z) = V_o * A/a(z) - \sum I_a(n) \text{ for } n=1 \text{ to } n=N, n \neq z$$

where

25 N = the number of subareas that each cell is splitted into,
 n = the index for subareas in the light sensor cell,
 a = the area of a subarea of the light sensor cell,
 V_o = the output signals from the light sensor cells,
 I_a = the computed light radiation received by the subarea a ,
30 z = the subarea to be used for calculation,
 A = the area of the light sensor cell.

20. An apparatus according to claim 17 or 18 or each of these claims in combination with claim 19, comprising that the apparatus further comprises a digital filter arranged for minimising the influence of at least one error in the value.

35 AMENDED SHEET (ARTICLE 19)

21. An apparatus according to claim 17 or 18 or each of these claims in combination with claims 19 or 20, comprising that the digital filter are using several values from several 5 cycles to compute a filter output value by the following formula

$$\begin{aligned}
 I_a(nX_A, mY_A) = & (F_{1,1}) * V_0(p_{(1)}X, q_{(1)}Y) - (F_{2,2}) * V_0(p_{(2)}X, q_{(2)}Y) - (F_{3,3}) * \\
 & \dots - (F_{A,A}) * V_0(p_{(A)}X, q_{(A)}Y) - (G_{-1,-0}) * I_a(n_{-1}X_A, m_{-0}Y_A) - (G_{-0,-1}) * \\
 10 & * I_a(n_{-0}X_A, m_{-1}Y_A) - (G_{-1,-1}) * I_a(n_{-1}X_A, m_{-1}Y_A) \\
 & \dots - (G_{-n,-m}) * I_a(n_{-n}X_A, m_{-m}Y_A),
 \end{aligned}$$

where,

15 - $I_a(nX_A, mY_A)$ is the light radiation value of the n,m'th element in the new X_A, Y_A matrix to be calculated,

- $I_a(n_{-1}X_A, m_{-0}Y_A)$ is the previous calculated element of the n-1,m'th element of the new X_A, Y_A matrix,

- $(G_{-1,-0})$ is the belonging predetermined filter value,

20 - $I_a(n_{-0}X_A, m_{-1}Y_A)$ is the previous calculated element of the n,m-1'th element of the new X_A, Y_A matrix,

- $(G_{-0,-1})$ is the belonging predetermined filter value,

- $I_a(n_{-n}X_A, m_{-m}Y_A)$ is the previous calculated element of the n-n, m-m'th element of the new X_A, Y_A matrix, $(G_{-n,-m})$ is the 25 belonging predetermined filter value,

- $V_0(p_{(1)}X, q_{(1)}Y)$ is the measured and stored output value of the p,q'th element in the physical sensor matrix overlapping the n,m'th element in the new calculated X_A, Y_A matrix from the first position,

30 - $(F_{1,1})$ is the belonging predetermined filter value,

- p,q are calculated from n/A and m/A,

- $V_0(p_{(A)}X, q_{(A)}Y)$ is the measured and stored output value of the p,q'th element in the physical sensor matrix overlapping the n, m'th element in the new calculated X_A, Y_A matrix from the A'th position,

35

- $(F_{A,A})$ is the belonging predetermined filter value, and p,q are calculated from n/A and m/A.

22. An apparatus according to claim 17 or 18 or each of these 5 claims in combination with claims 19, 20 or 21, comprising that the computer (23;35) is provided with a software program for establishing a representation of the high resolution image by calculating the representation of the received incident light from the scene at each subarea.

10 23. An apparatus according to claims 17 or 18 or each of these claims in combination with any of the claims 19 - 22, with means for providing an identifiable coding of the position of the light sensor (18) mounted on the sensor frame (20) 15 into the low resolution first image.

20 24. An apparatus according to claim 23, comprising that the means for providing the identifiable coding of the position of the light sensor (18) mounted on the sensor frame (20) into the low resolution first image comprise of a program that uses some of the pixels in the scanned image and substitutes these with information about said position.

25 25. An apparatus according to claim 17 or 18 or each of these claims in combination with any of the claims 19 - 24, comprising that the predetermined curve is formed as a triangle or a stairway or is sinusoidal.

30 26. An apparatus according to claim 17 or 18 or each of these claims in combination with any of the claims 19 - 25, comprising that the light sensor (18) is moved in system of x-y co-ordinates and moved at least in one of the x-y directions.

35 27. An apparatus according to each of the claim 17 or 18 or each of these claims in combination with any of the claims

19 - 26, comprising that the at least one driver (21;33;39,40) is an electro-mechanical device or a piezoelectric-element.

5 28. An apparatus according to claim 17 or 18 or each of these claims in combination with any of the claims 19 - 27, wherein the at least one driver (21;33) comprise a coil (39) rigidly mounted on a base frame (37) and an anchoring means (40) mounted on the sensor frame (20), said sensor frame 10 being moveable mounted on the base frame, and said anchoring means to be actuated by an attractive force induced by the coil and thereby pulling the anchor toward the coil.

29. A use of the method according to claims 1 - 16 and the 15 apparatus according to claims 17 - 28 in a web camera or a still picture camera or camcorder or a monitoring camera or a 360° camera or a digital binocular glasses or a scanner.

1/11

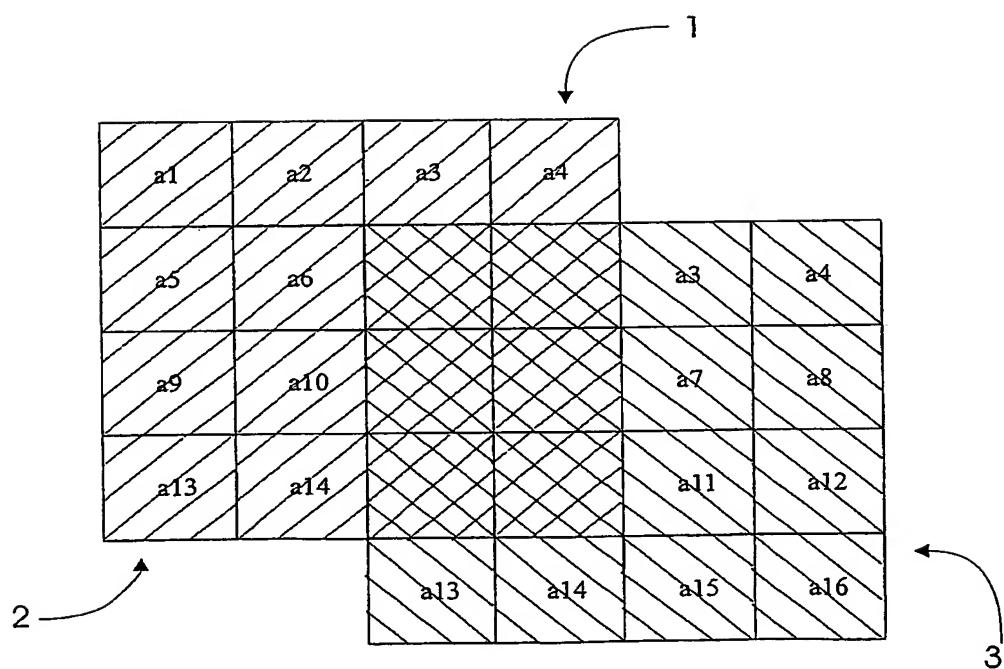


Fig.1

2/11

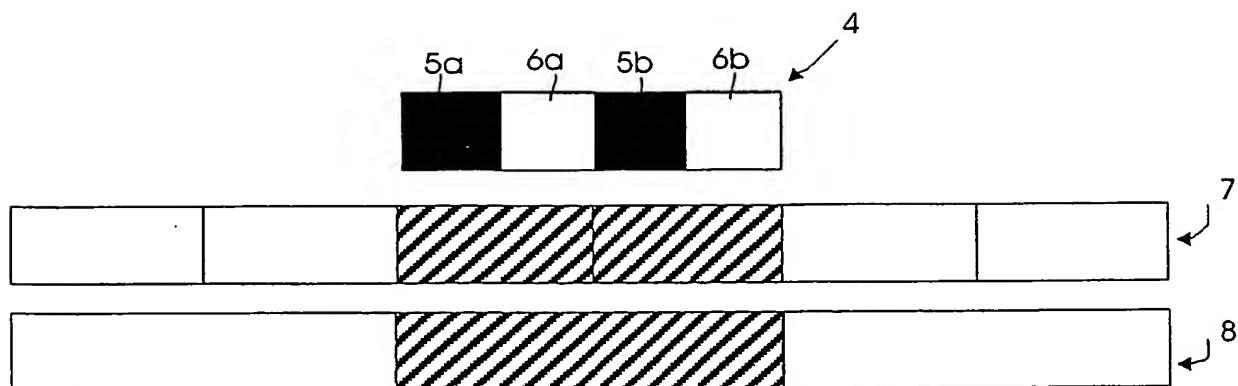


Fig. 2a

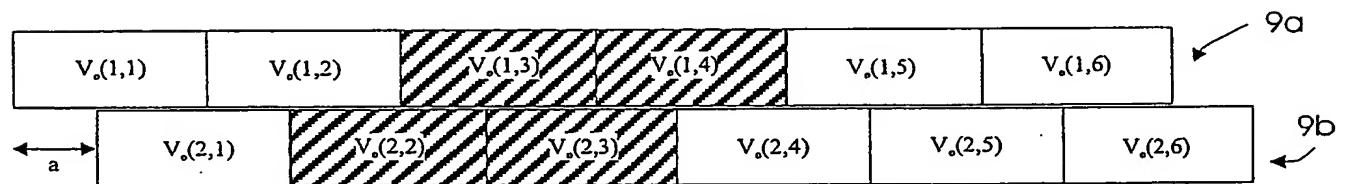


Fig. 2b

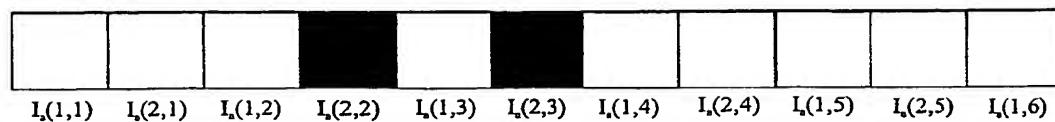


Fig. 2c

3/11

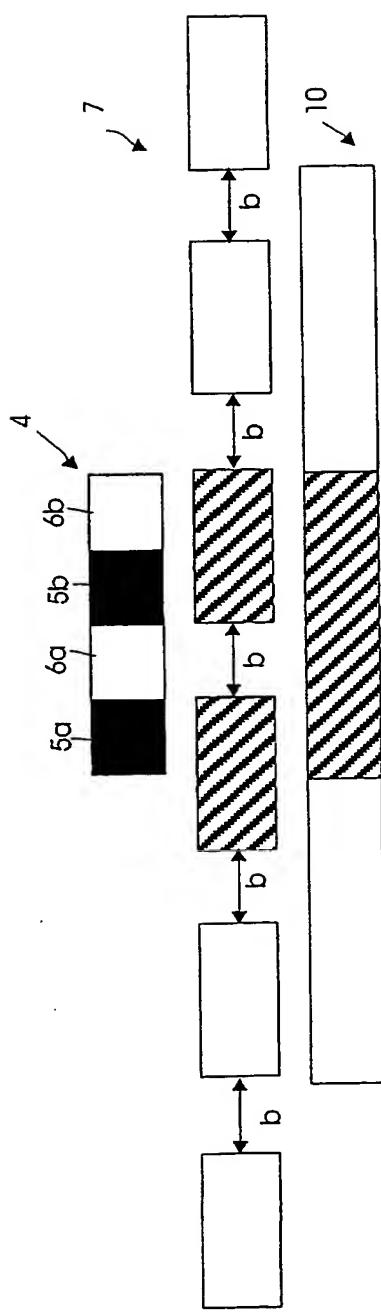


Fig. 3a

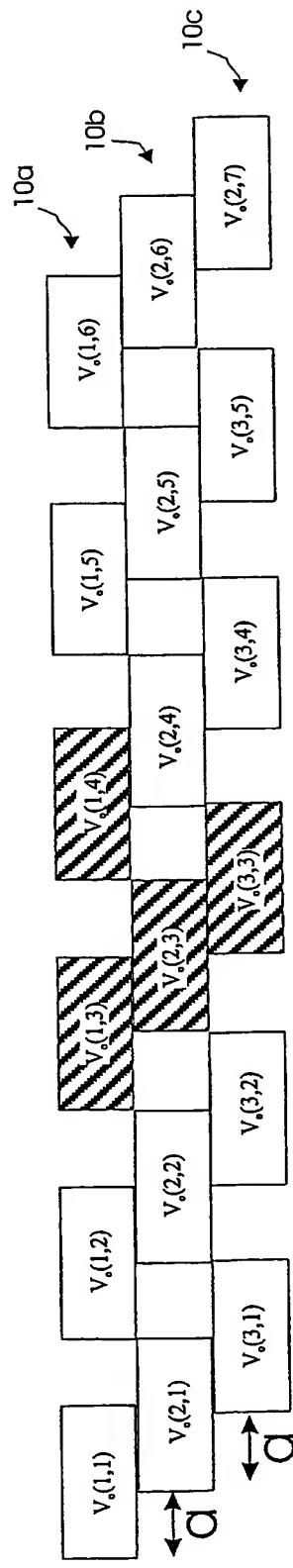


Fig. 3b

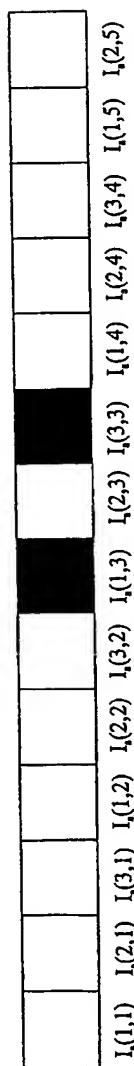


Fig. 3C

4/11

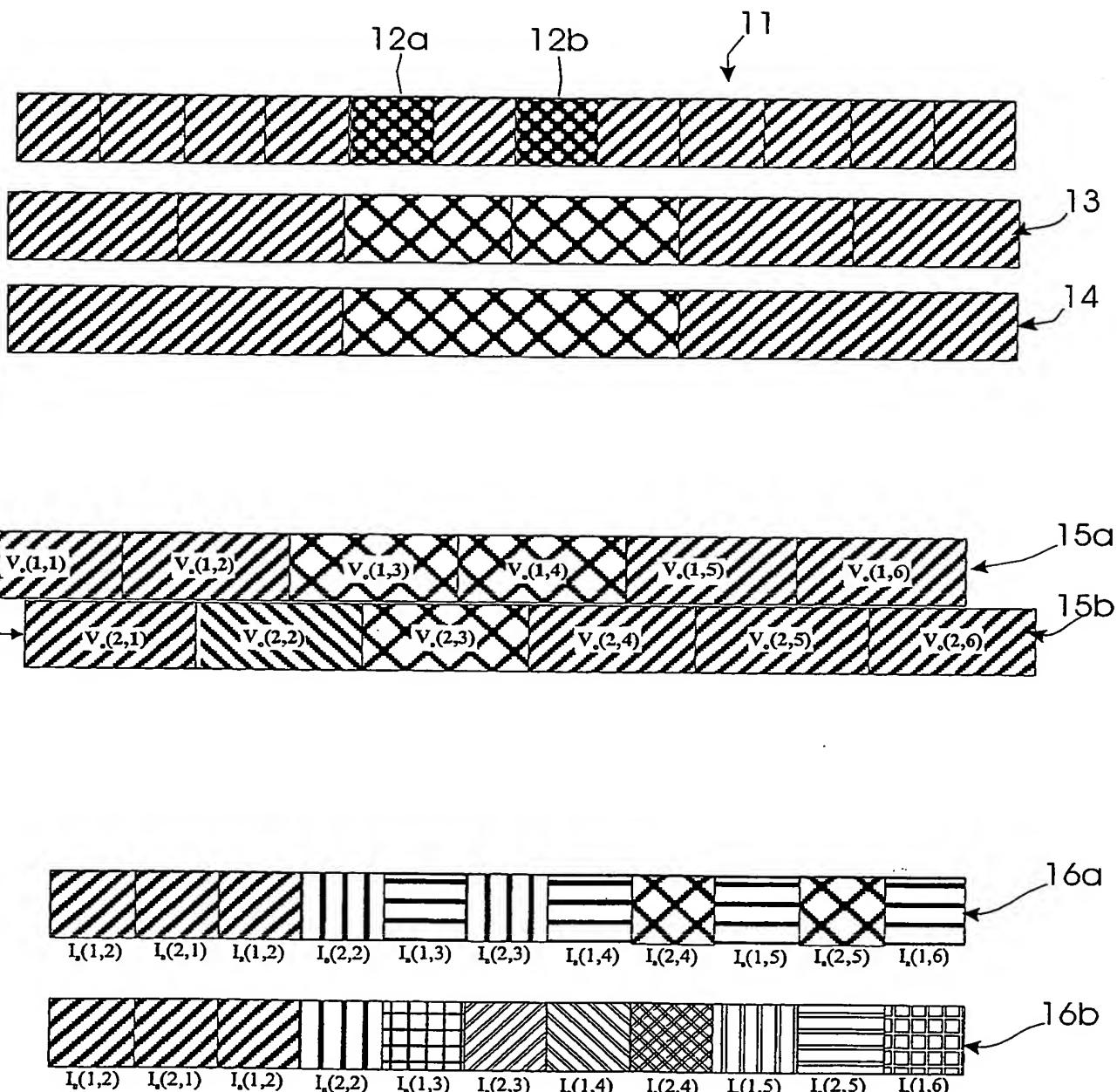


Fig. 4

5/11

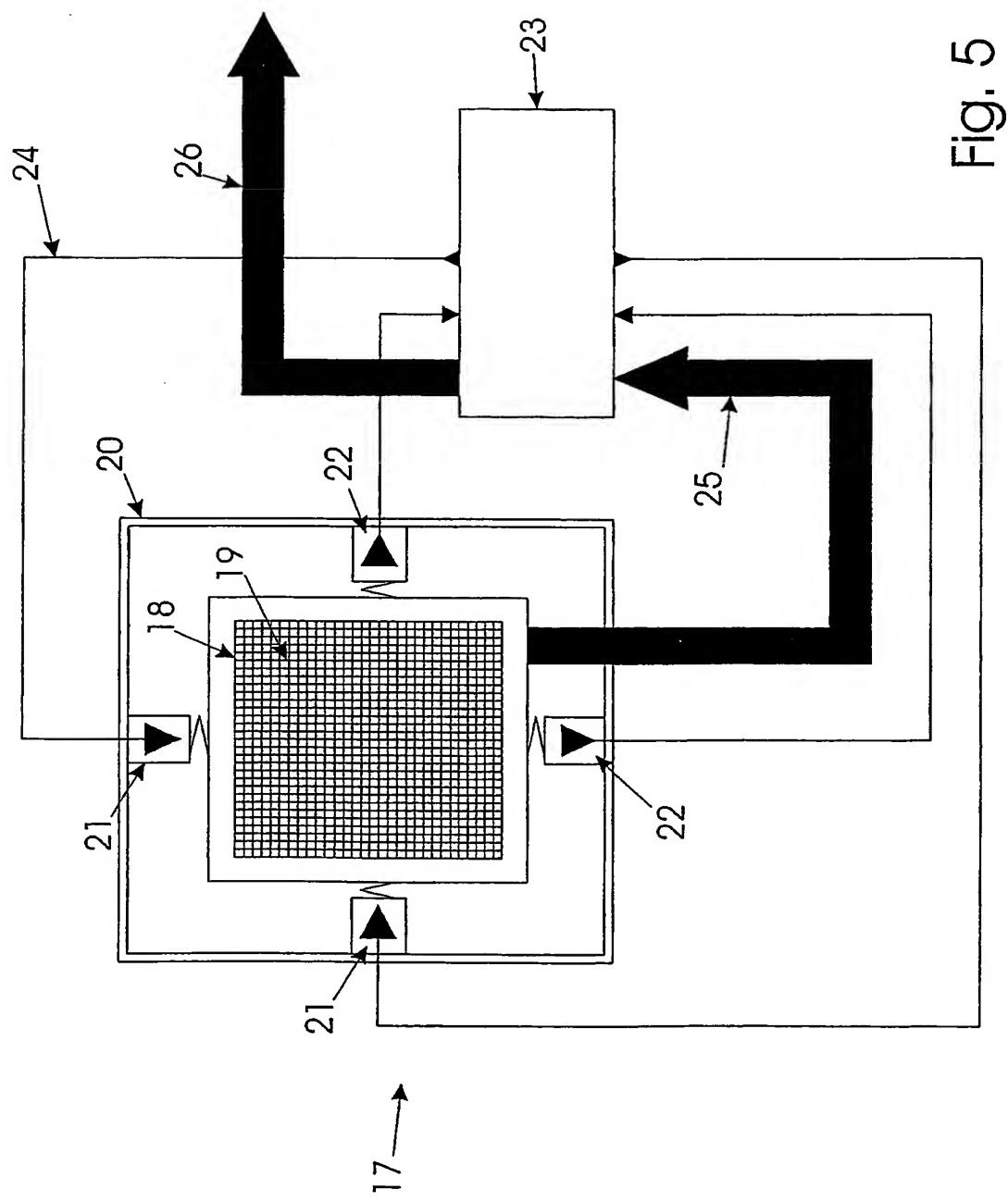


Fig. 5

6/11

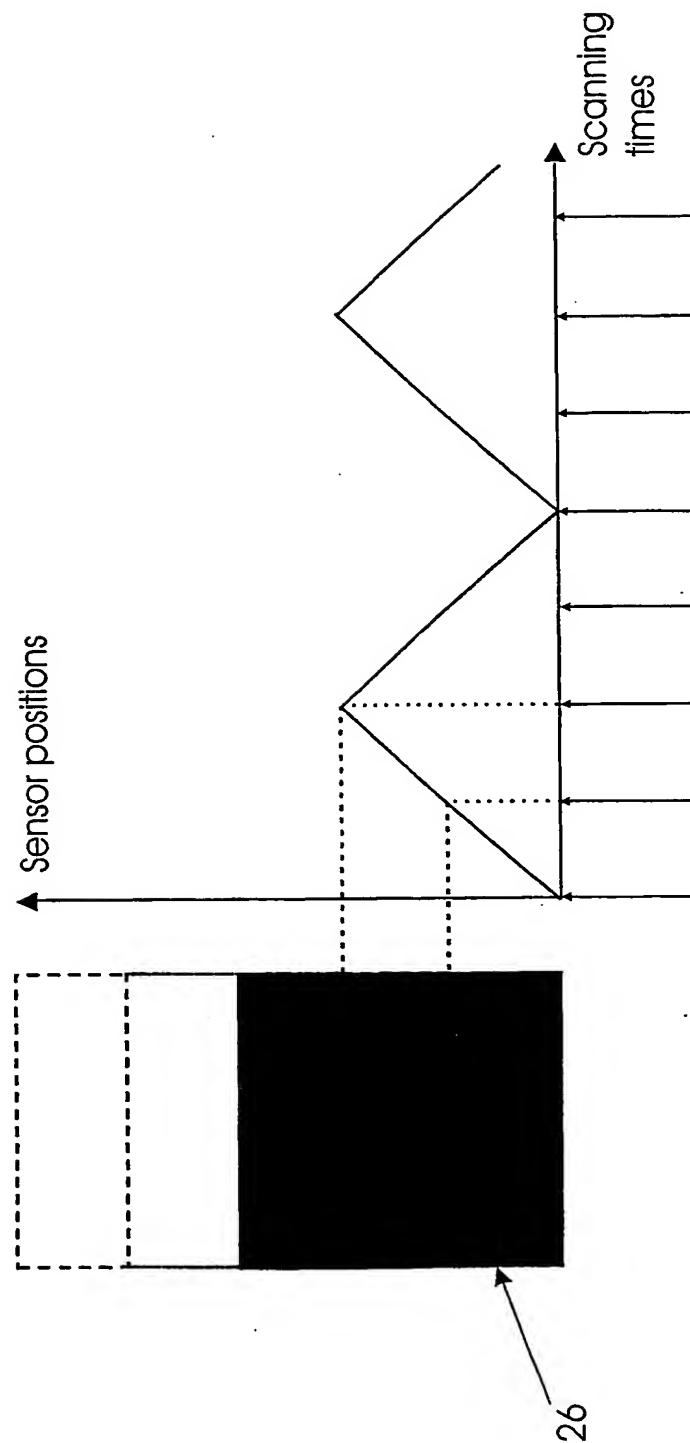


Fig. 6a

Fig. 6b

7/11

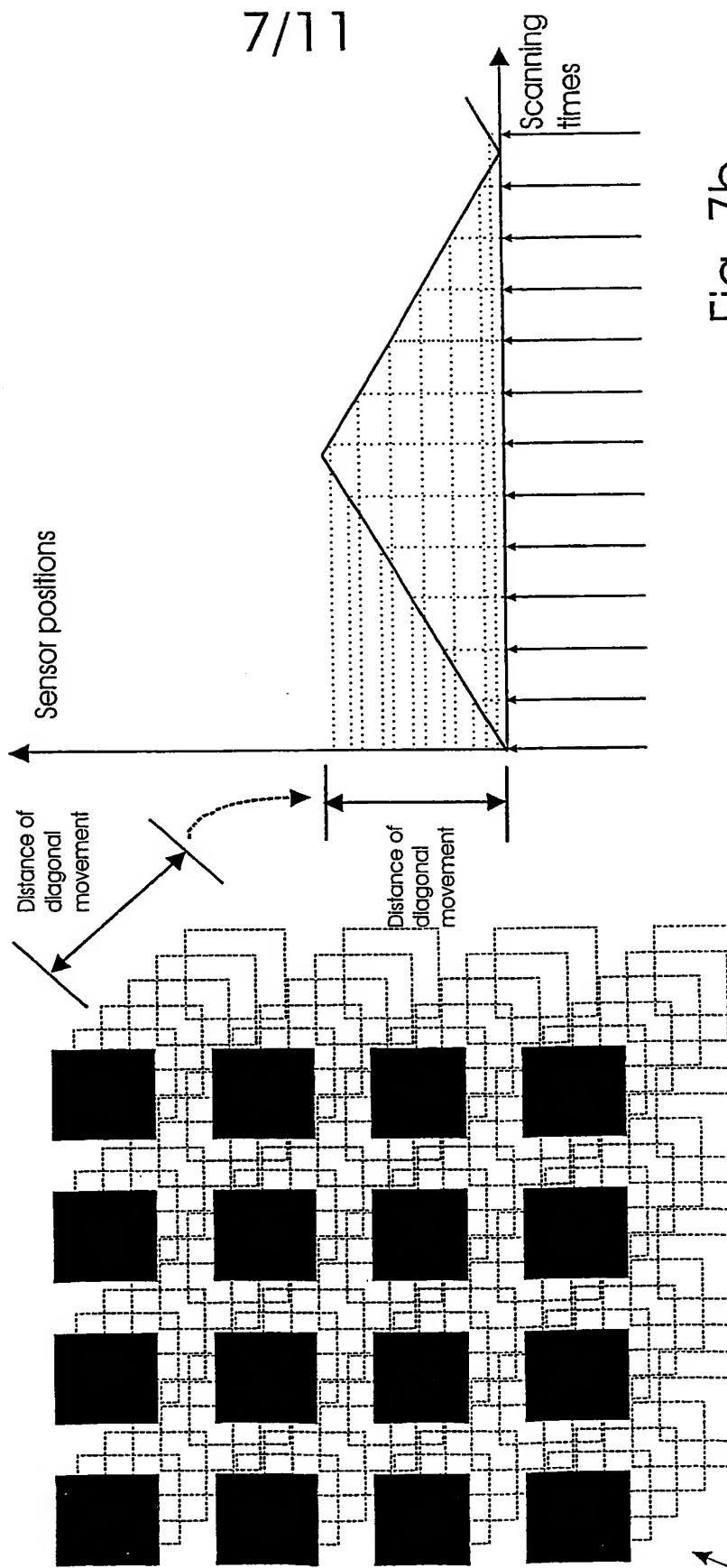


Fig. 7b

Fig. 7a

8/11

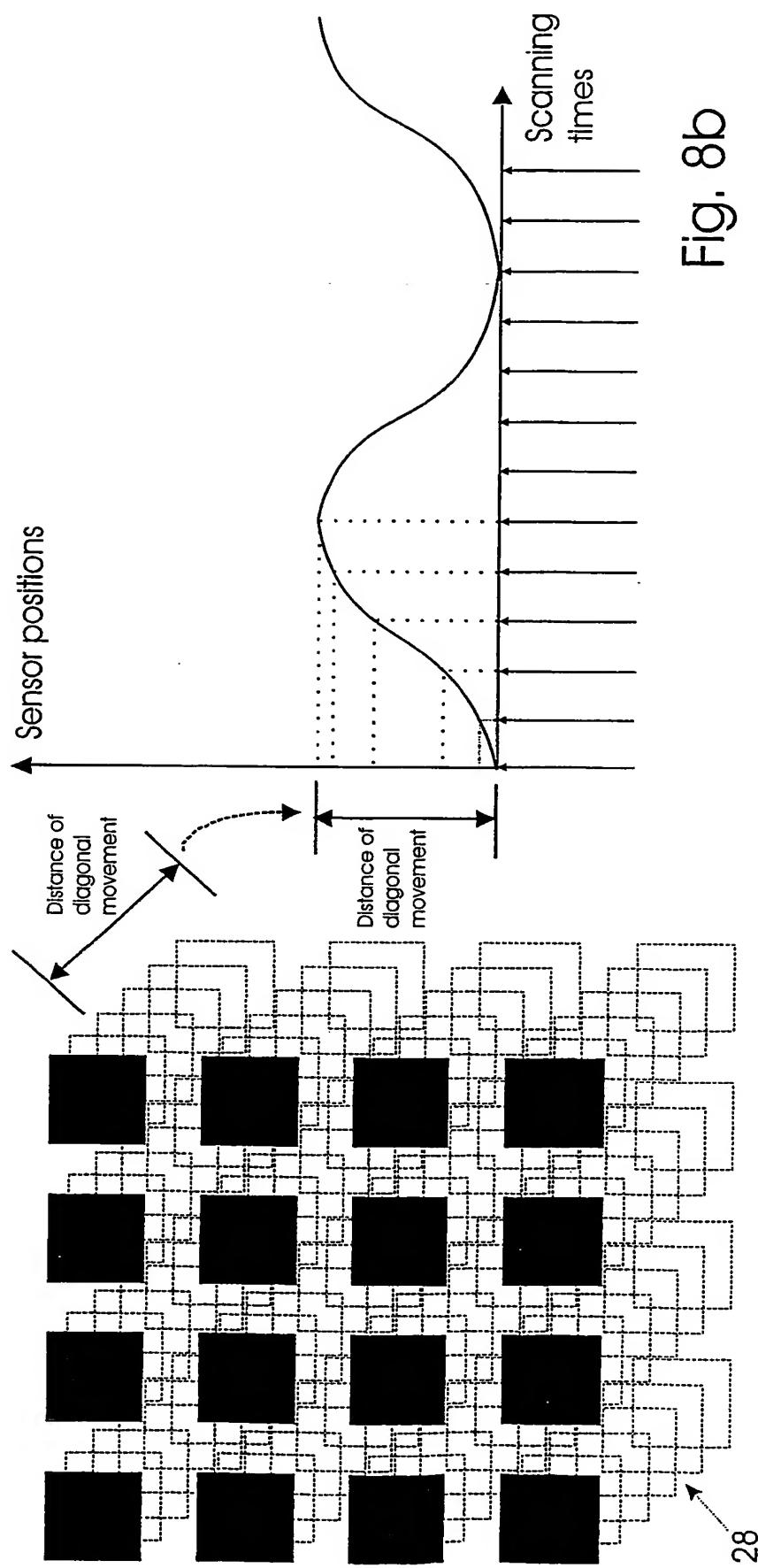


Fig. 8a

Fig. 8b

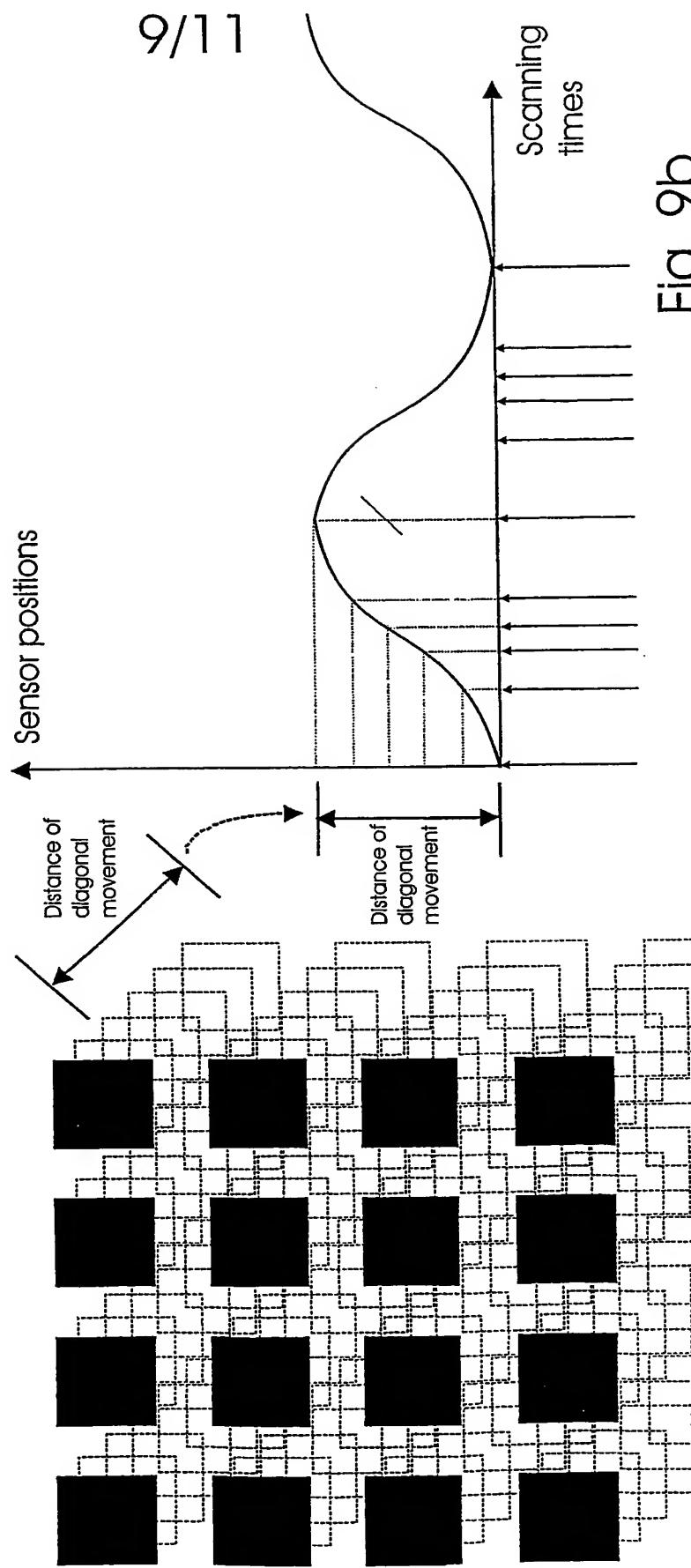


Fig. 9b

Fig. 9a

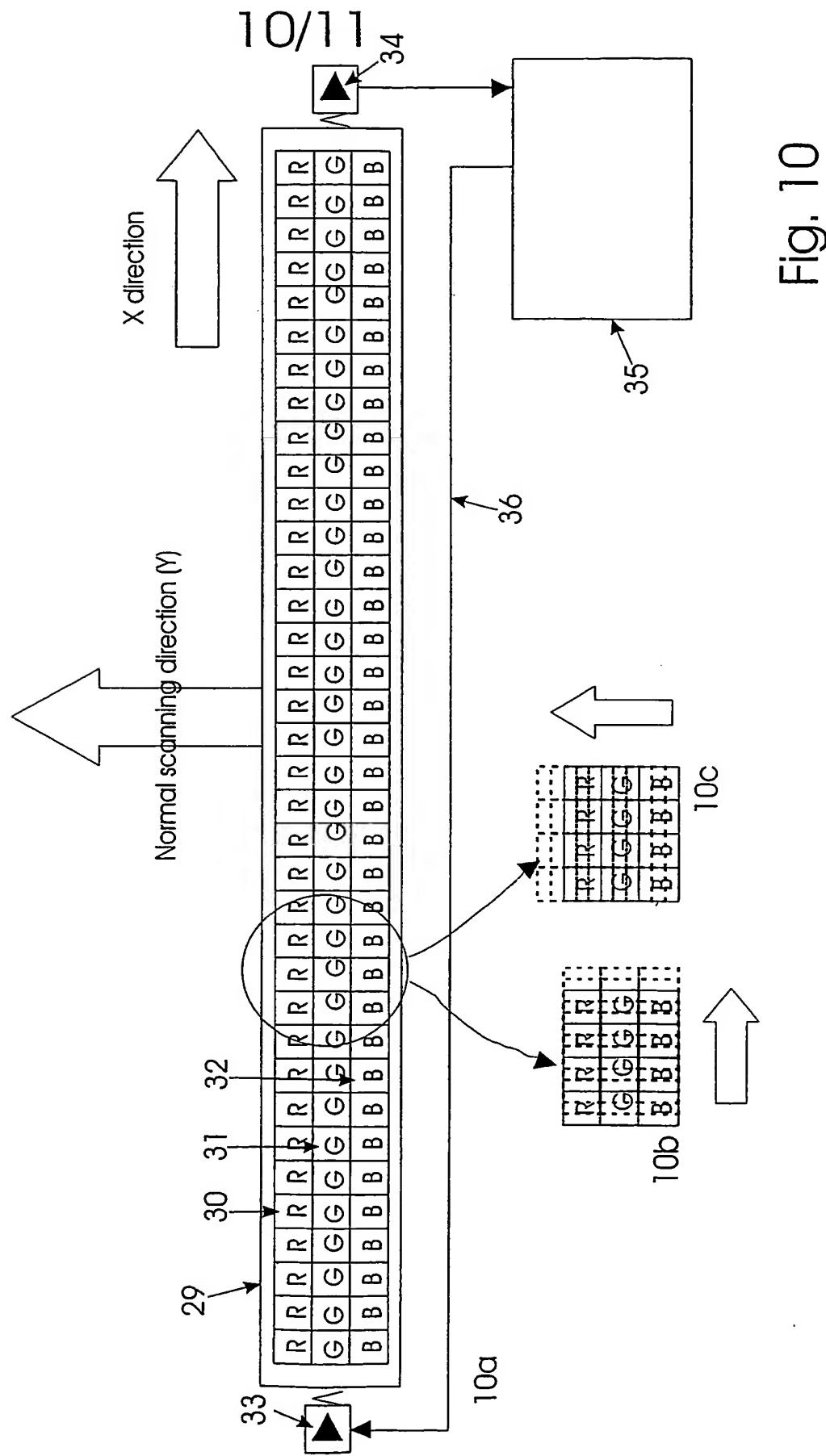


Fig. 10

11/11

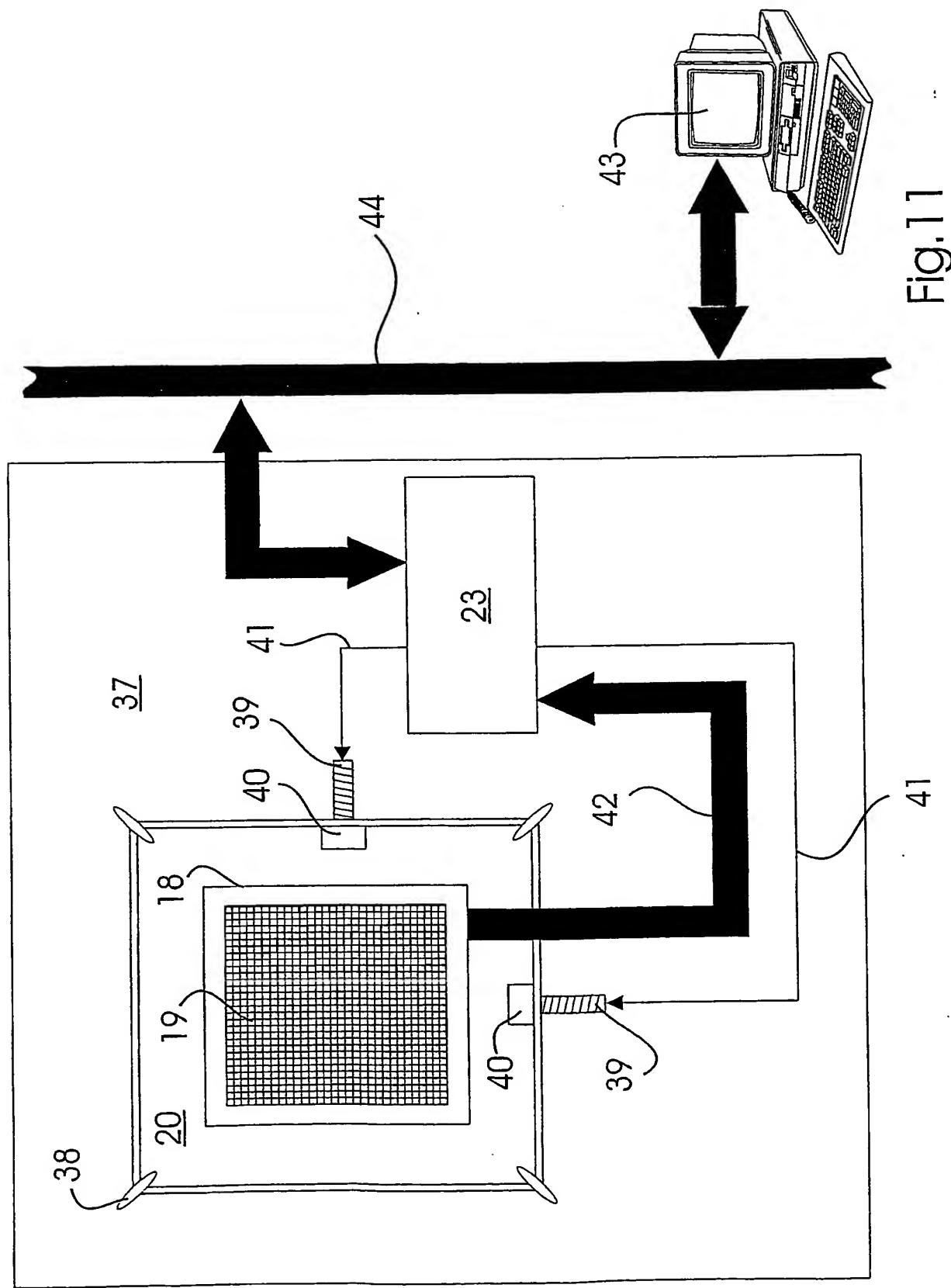


Fig. 11

INTERNATIONAL SEARCH REPORT

International Application No
PCT/DK 02/00589

A. CLASSIFICATION OF SUBJECT MATTER
IPC 7 H04N3/15

According to International Patent Classification (IPC) or to both national classification and IPC

B. FIELDS SEARCHED

Minimum documentation searched (classification system followed by classification symbols)
IPC 7 H04N

Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched

Electronic data base consulted during the international search (name of data base and, where practical, search terms used)

EPO-Internal, PAJ

C. DOCUMENTS CONSIDERED TO BE RELEVANT

Category	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
X	WO 97 12483 A (ELONEX TECHNOLOGIES INC) 3 April 1997 (1997-04-03) cited in the application page 2, line 33 -page 3, line 8 page 6, line 1 - line 10 page 8, line 27 -page 9, line 19	1-4, 7-9, 11, 12, 17, 18, 24, 25
A	-----	5, 19



Further documents are listed in the continuation of box C.



Patent family members are listed in annex.

* Special categories of cited documents:

- *A* document defining the general state of the art which is not considered to be of particular relevance
- *E* earlier document but published on or after the international filing date
- *L* document which may throw doubts on priority claim(s) or which is cited to establish the publication date of another citation or other special reason (as specified)
- *O* document referring to an oral disclosure, use, exhibition or other means
- *P* document published prior to the international filing date but later than the priority date claimed

- *T* later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention
- *X* document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone
- *Y* document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art.
- *8* document member of the same patent family

Date of the actual completion of the international search

31 October 2002

Date of mailing of the international search report

08/11/2002

Name and mailing address of the ISA

European Patent Office, P.B. 5818 Patentlaan 2
NL - 2280 HV Rijswijk
Tel. (+31-70) 340-2040, Tx. 31 651 epo nl,
Fax: (+31-70) 340-3016

Authorized officer

Bequet, T

INTERNATIONAL SEARCH REPORT

Information on patent family members

International Application No

PCT/DK 02/00589

Patent document cited in search report	Publication date	Patent family member(s)	Publication date
WO 9712483	A 03-04-1997	WO 9712483 A1	03-04-1997

Form PCT/ISA/210 (patent family annex) (July 1992)

CORRECTED VERSION

(19) World Intellectual Property Organization International Bureau



(43) International Publication Date
17 April 2003 (17.04.2003)

PCT

(10) International Publication Number
WO 2003/032627 A1

(51) International Patent Classification⁷: H04N 3/15 Ørsted [DK/DK]; Gulddyssevænget 3, Gundsømagle, DK-4000 Roskilde (DK).

(21) International Application Number: PCT/DK2002/000589 (74) Agent: HOLME PATENT A/S; Vesterbrogade 20, DK-1620 Copenhagen V (DK).

(22) International Filing Date: 11 September 2002 (11.09.2002) (81) Designated States (national): AE, AG, AL, AM, AT (utility model), AT, AU, AZ, BA, BB, BG, BR, BY, BZ, CA, CH, CN, CO, CR, CU, CZ (utility model), CZ, DE (utility model), DE, DK (utility model), DK, DM, DZ, EC, EE (utility model), EE, ES, FI (utility model), FI, GB, GD, GE, GH, GM, HR, HU, ID, IL, IN, IS, JP, KE, KG, KP, KR, KZ, LC, LK, LR, LS, LT, LU, LV, MA, MD, MG, MK, MN, MW, MX, MZ, NO, NZ, OM, PH, PL, PT, RO, RU, SD, SE, SG, SI, SK (utility model), SK, SL, TJ, TM, TN, TR, TT, TZ, UA, UG, US, UZ, VC, VN, YU, ZA, ZM, ZW.

(25) Filing Language: English

(26) Publication Language: English

(30) Priority Data: PA 2001 01326 11 September 2001 (11.09.2001) DK (84) Designated States (regional): ARIPO patent (GH, GM, KE, LS, MW, MZ, SD, SL, SZ, TZ, UG, ZM, ZW), Eurasian patent (AM, AZ, BY, KG, KZ, MD, RU, TJ, TM), European patent (AT, BE, BG, CH, CY, CZ, DE, DK, EE, ES, FI, FR, GB, GR, IE, IT, LU, MC, NL, PT, SE, SK,

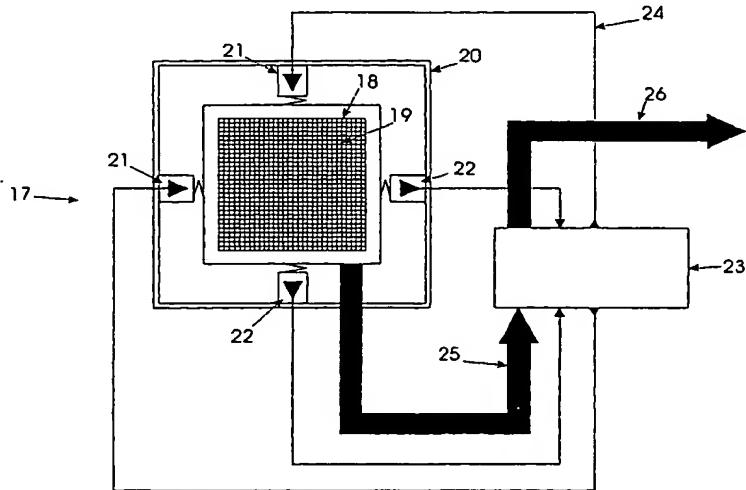
(71) Applicant (for all designated States except US): DELTAPIX APS [DK/DK]; Gulddyssevænget 3, Gundsømagle, DK-4000 Roskilde (DK).

(72) Inventor; and

(75) Inventor/Applicant (for US only): ANDERSEN, Steen,

[Continued on next page]

(54) Title: A METHOD AND APPARATUS FOR PRODUCING A HIGH RESOLUTION IMAGE



WO 2003/032627 A1

(57) Abstract: A method and apparatus serves for converting a low resolution first image to a high resolution second image. The apparatus is comprising a light sensor (1, 19) for receiving incident light radiated from a scene. The light sensor has a number of cells, each defining a predetermined area, and is arranged for cyclically scanning the low resolution first image a number of times while at least one driver (21, 33, 39, 40) is moving the light sensor an identical number of times in at least one direction. For each step the light sensor is moved a distance corresponding to the extend of the area covered by the cell in the direction of movement while the total distance covered corresponds to the extend of the cell in said direction. Thereby a number of subareas are defined. A computer (23, 35) serves for establishing a representation of the high resolution second image by calculating the representation of the received incident light from the scene at each subarea by means of a soft ware program. Thereby is obtained a higher resolution and a better image quality than hitherto known.



TR), OAPI patent (BF, BJ, CF, CG, CI, CM, GA, GN, GQ,
GW, ML, MR, NE, SN, TD, TG).

(15) Information about Correction:

see PCT Gazette No. 48/2004 of 25 November 2004, Section II

Published:

- with international search report*
- with amended claims*

(48) Date of publication of this corrected version:

25 November 2004

For two-letter codes and other abbreviations, refer to the "Guidance Notes on Codes and Abbreviations" appearing at the beginning of each regular issue of the PCT Gazette.

**This Page is Inserted by IFW Indexing and Scanning
Operations and is not part of the Official Record**

BEST AVAILABLE IMAGES

Defective images within this document are accurate representations of the original documents submitted by the applicant.

Defects in the images include but are not limited to the items checked:

- BLACK BORDERS**
- IMAGE CUT OFF AT TOP, BOTTOM OR SIDES**
- FADED TEXT OR DRAWING**
- BLURRED OR ILLEGIBLE TEXT OR DRAWING**
- SKEWED/SLANTED IMAGES**
- COLOR OR BLACK AND WHITE PHOTOGRAPHS**
- GRAY SCALE DOCUMENTS**
- LINES OR MARKS ON ORIGINAL DOCUMENT**
- REFERENCE(S) OR EXHIBIT(S) SUBMITTED ARE POOR QUALITY**
- OTHER:** _____

IMAGES ARE BEST AVAILABLE COPY.

As rescanning these documents will not correct the image problems checked, please do not report these problems to the IFW Image Problem Mailbox.

This Page Blank (uspto)